

ROSETTA: Constructing Code-Based Reward from Unconstrained Language Preference

Sanjana Srivastava^{1*}, Kangrui Wang^{2*}, Yung-Chieh Chan^{1*}, Tianyuan Dai¹,
Manling Li², Ruohan Zhang¹, Mengdi Xu¹, Jiajun Wu¹, Li Fei-Fei¹

¹Department of Computer Science, Stanford University, Stanford, CA 94305

²Department of Computer Science, Northwestern University, Evanston, IL 60208

*Equal contribution. Correspondence: sanjana2@cs.stanford.edu

Abstract—Intelligent embodied agents not only need to accomplish preset tasks, but also learn to align with individual human needs and preferences. Extracting reward signals from human language preferences allows an embodied agent to adapt through reinforcement learning. However, human language preferences are unconstrained, diverse, and dynamic, making constructing learnable reward from them a major challenge. We present ROSETTA, a framework that uses foundation models to ground and disambiguate unconstrained natural language preference, construct multi-stage reward functions, and implement them with code generation. Unlike prior works requiring extensive offline training to get general reward models or fine-grained correction on a single task, ROSETTA allows agents to adapt online to preference that evolves and is diverse in language and content. We test ROSETTA on both short-horizon and long-horizon manipulation tasks and conduct extensive human evaluation, finding that ROSETTA outperforms SOTA baselines and achieves 87% average success rate and 86% human satisfaction across 116 preferences.

I. INTRODUCTION

Human-centered embodied intelligence requires that humans be able to guide embodied agents to align with their preferences [3, 21]. For agents operating in closed-loop interactions, this means aligning with each human preference in its most natural and unconstrained forms [23], as shown in Fig. 1. Reinforcement learning (RL)-based embodied agents have demonstrated the ability to adapt to high-level tasks originating in human language given dense rewards [45], and the efficiency of specifying reward rather than collecting extensive training data makes RL a promising testbed. However, humans have unique voices and changing goals. Adaptation requires handling unconstrained language and unseen goals that edit, build on, or even contradict prior goals at every step. Generating effective rewards under such conditions is an open problem.

Reward modeling enables creation of nuanced reward signals without expert shaping. While many existing methods are general and multi-task, often able to adapt to changing, unseen goals, they require extensive end-to-end training [5, 2]. Due to their large-scale training across diverse domains, foundation models [4] offer a compelling alternative to custom reward model training. Their code generation capabilities offer a natural conduit between language and dense scalar reward. However, prior methods like Eureka [31] and Text2Reward [54] that work for embodied agent manipulation are limited to clean

and structured language, predetermined goals that remain fixed over the course of interaction with the human, and several rounds of feedback that aims only to refine that fixed goal, rather than assert the human’s own evolving preferences and receive immediate adaptation.

In this paper, we aim to generate rewards for language preferences that do not obey these constraints. First, **the underlying tasks requested in these preferences are not cleanly phrased**. Individuals express themselves in whatever way is natural and efficient. Second, **the preferences have dynamic and unseen content that requires single-step adaptation**. This means that whatever goal comes up, we aim for a good reward function in a single step. And third, **evaluation of adaptation to naturally expressed preferences is itself a bottleneck**. It is impossible to measure alignment with training metrics such as success rates alone, as they do not address adherence to the preference, only to the goal in the reward function which may not match the preference.

To address these challenges, we ROSETTA (Fig. 2): Reward Objectives from Spontaneous Expression Translated to Agents. ROSETTA is a code-based reward generation pipeline that enables embodied agent adaptation to human natural language preference in a single step. ROSETTA generates rewards from chains of single preference statements that have no constraints on language, limited constraints on content, and adapt to each preference in ongoing interactions. It contains a **Preference Grounding** module to disambiguate unconstrained human preference and contextualize it in prior preferences and the prior policy’s task execution, as well as a **Staging** module that repurposes LLMs’ known planning abilities [16] to add structure and create staged rewards. Both of these happen in language space using gpt-4o [34]. The **Coding** module then turns the staged reward specification into coded reward function. ROSETTA uses o1-mini [35]. ROSETTA therefore generates rewards even from preferences that change the entire shape of a task in just a few words.

We also propose an evaluation framework consisting of three key metric categories. Most important is **alignment**, measuring human satisfaction with the policy. Measuring alignment requires direct human input [8, 10], but can be noisy and incomplete, motivating additional metrics. First, we do also want rewards that are suitable for RL. We therefore



Fig. 1: ROSETTA’s three-module structure takes unconstrained, unseen natural language preference and generates reward code that incentivizes desired behavior. ROSETTA can adapt to diverse behavioral preferences, not only in position but orientation and speed. We validate ROSETTA’s performance in two short-horizon and three long-horizon task-agnostic environments.

measure reward **optimizability** via policy success rate. Second, we want to know if the generated reward reflects the stated human preference. Using only the trained policy introduces confounds: the reward function may match semantics but not be optimizable. We therefore directly measure **semantic match**, measured by expert evaluation of the reward code itself.

We validate ROSETTA iteratively: multiple steps of taking a language preference, generating a reward, training an agent, evaluating, and obtaining a new preference. We evaluate ROSETTA on 35 sequences of two to four preferences each, total 116 preferences, in five task-agnostic manipulation environments (Fig. 1). ROSETTA successfully interprets ambiguous language, adapts to unseen preferences even after four interaction steps, and produces semantically matched and optimizable rewards that result in aligned policies. As seen in Sec. V-B, it outperforms Eureka and Text2Reward, demonstrating the importance of its structured approach for immediate and general adaptation. In summary, we present three main contributions:

- ROSETTA, a foundation model-based method generating code-based rewards that enables robots adapting to unconstrained, diverse, dynamic human preferences online.
- An evaluation framework for measuring human-embodied agent interactions in the wild, consisting of metrics for alignment, semantic match and optimizability.
- Evaluation in five tasks on 116 human preferences, showing ROSETTA’s SOTA performances: 86% human satisfaction, 78% semantic match, and 87% success rate. It shows 33% better human satisfaction than baselines.

II. RELATED WORK

a) Foundation models on human-robot interaction and control.: foundation models have transformed the landscape of robotics by enabling natural language interaction. Early works focused on affordances and executable control code [1, 26, 17, 43], establishing the foundation for language-guided robotics. Recent work has explored more interactive paradigms,

developing systems that can interpret and incorporate real-time verbal feedback and corrections during task execution [9, 29, 56, 41, 42, 27]. These interactive approaches have been further extended to handle complex spatial reasoning and hierarchical task planning [18, 22, 49, 44, 6]. The field has also seen significant advances in open-ended embodied control and personalized human-robot interaction systems [51, 57, 52, 24].

b) LLMs for reward engineering.: The most relevant developments to our work lie in the direct application of LLMs for reward engineering. Recent approaches have demonstrated increasingly sophisticated methods for translating natural language into reward functions, ranging from basic reward shaping to full code generation [53, 31, 55, 25]. Some approaches have explored automated reward generation through progress functions [39] or evolutionary techniques guided by human feedback [15]. These methods require a fixed task definition. They also require pre- and hand-defined goal-specific supervision like fitness functions or goal-specific information.

While existing approaches require either pretraining or fixing the goal and using only directly helpful feedback, ROSETTA enables reward generation for unconstrained, dynamic goals without training. This is a significant step toward embodied agents that adapt to novel instructions. The core innovation lies in our structured and domain knowledge-informed generation.

III. PROBLEM FORMULATION

Our aim is to turn human language preferences into semantically matched, optimizable reward functions that will lead to aligned embodied agent policies, even in ongoing interactions where preferences compound. We aim to do so for ongoing chains of preferences, adapting to each individual preference while also adapting to the compounding meaning over time and avoiding degradation in later interactions. We formulate it as the reward generation problem for unconstrained human language preference adaptation, extending the reward generation problem presented in [31]. The reward generation

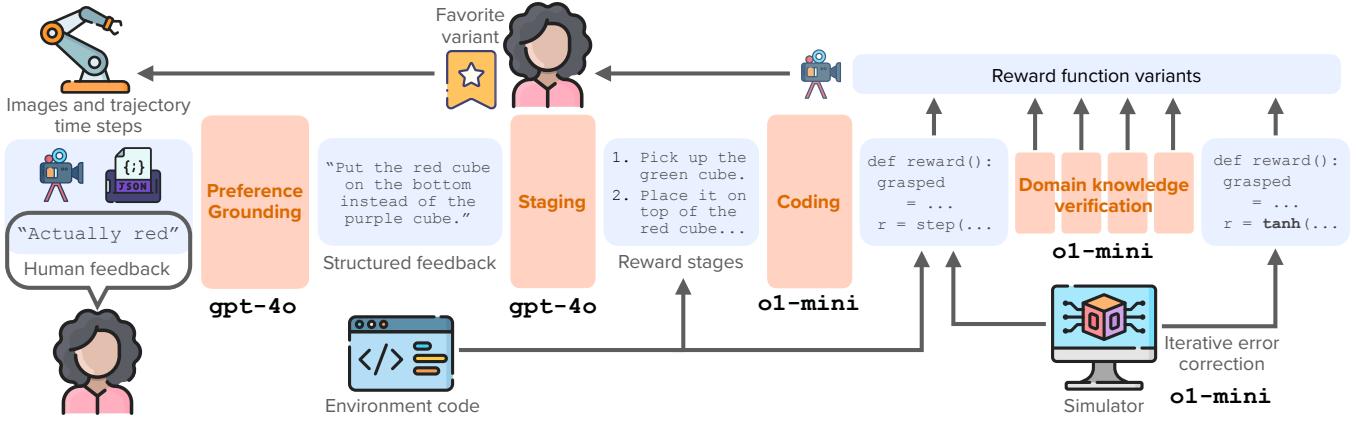


Fig. 2: ROSETTA diagram. A trajectory from the latest policy and preference history are given to the Preference Grounding module. The resulting grounded preference is given to the Staging module. The Coding module takes resulting staged reward plan and generates reward variants with various domain knowledge reasserted. Iterative error correction conducted.

problem [31] takes a task description l and generates a reward function R that maximizes a known fitness function $\bar{F}(\mathcal{A}_M(R))$, where $\mathcal{A}_M(R)$ is a learning algorithm run on world model M and reward R to get policy π . The fitness function \bar{F} is known when the task goal is predetermined and does not change. However when adapting to unconstrained human preferences, the fitness function denoted as $F^{(t)}$ is instead unknown and time-dependent. It can be used to aid the adaptation process across different t , but unlike in Eureka or Text2Reward, we do not assume this. We aim for each $F^{(t)}$ to be maximized, so that we minimize user queries for any goal.

a) *Reward generation for unconstrained human language preference adaptation.*: An adaptive embodied agent interacts with humans through multiple iterations of preference. At preference iteration $t = 0$, the agent $\pi^{(0)}$ is trained to optimize a given task with a text description $l^{(0)}$. Then at any following preference iteration $t \in [1, T]$, a human preference annotator watches a rollout of policy $\pi^{(t-1)}$ and gives language preference $h^{(t)}$. Given the latest policy $\pi^{(t-1)} := \mathcal{A}_M(R^{(t-1)})$ and history of human preference $\{l^{(0)}, h^{(1)}, \dots, h^{(t)}\}$, the objective is to output a reward function $R^{(t)}$ such that $F^{(t)}(\mathcal{A}_M(R^{(t)}))$ is maximized. In this problem, $F^{(t)}(\cdot)$ is the **human's satisfaction level** with a task execution controlled by $\pi^{(t)} := \mathcal{A}_M(R^{(t)})$. We once again note the importance of maximizing $F^{(t)}$ at every t , rather than using multiple $h^{(t)}$ to maximize one \bar{F} .

A. Evaluation Framework

It is ultimately human satisfaction that matters, meaning we need to measure a complex, noisy quantity that itself is given on the policy rollout video, a variable and open-ended stimulus. ROSETTA's reward functions need to be evaluated for semantic match and optimizability. We therefore propose three sets of metrics on the set of reward functions detailed as follows.

Alignment requires a thorough human survey. We propose a) binary and ternary descriptive questions regarding the preference, such as ‘‘did the robot incorporate your preference that wasn't met in the previous video,’’ ‘‘did the robot contradict any part of your preference in the current video,’’ etc. b) Binary and Likert questions that quantify satisfaction [20]. Full survey

text is in Sec. J. **Semantic match** requires establishing that the goal in the generated code matches the goal in the preference. Given that reward code is a long-form generation and therefore difficult to objectively evaluate [38], we propose expert text evaluation. ROSETTA's preference-code pairs are evaluated by roboticists, also with binary and Likert questions such as ‘‘does the reward function miss part or all of the reward plan’’ or ‘‘are there common sense errors’’. Full survey text is in Sec. J. **Optimizability** measures whether the generated reward function is suitable for the learning algorithm $\mathcal{A}_M(\cdot)$. We use the success rate on evaluation rollouts to tell us how well the reward function can be optimized given adequate models and training algorithms.

IV. APPROACH

We introduce ROSETTA, which is made of three prompt-based modules: Preference Grounding, Staging, and Coding. As seen in Fig. 2, these modules are built on each other to get the final reward function. All prompts are included in Sec. D.

Preference Grounding. Generating rewards from unconstrained human language preference first requires that the preference be contextualized and disambiguated. Foundation models rely on the letter of the prompt, so the system needs to match vague references, consider prior preferences, etc. For example, consider ‘‘no, get it to the center.’’ ‘‘it’’ needs to be mapped to `self.obj`. ‘‘center’’ needs to be mapped to ‘‘center of `self.target`’’. Even ‘‘get’’ could be mapped to ‘‘push’’. This preference was given on a reward function that already aimed for the agent to push the ball to the center, so the ‘‘no’’ needs to be recognized as rejection of the performance but not of the goal. Finally, the previous preference was ‘‘can it start further back?’’ and this needs to be retained despite not being mentioned. We therefore introduce a Preference Grounding module that uses trajectory images, symbolic states, and a single-sentence task description to get per-step language descriptions. From these, it generates a summary of task performance, grounded human preference, and a new single-sentence goal for use in the next interaction step. The above

example becomes “the agent did not push the ball to the center of the target as requested. It should do so while still starting further back.” Here we use gpt-4o [34] given its strong vision-language capabilities.

Staging. In unconstrained language preference, a single sentence can completely change the task goal without providing guidance on steps to take. However, dense reward often requires breaking the task into stages and rewarding each one. We automate staging by leveraging its similarity to task-planning. foundation models are adept at planning [16], and unlike many settings that require fixed output structure, here we can allow the foundation model to stage in language space and capture nuances embedded in the language. Given “nestle the ball into the bin”, the Staging module generates a plan including “Stage 3: Reward the agent for placing the ball in the corner of the bin with a tight threshold”. These function as concrete design notes for the Coding module. The Staging module takes four inputs: existing environment code, generated task description, generated agent summary, and grounded preference. As in [31], the environment code gives context for scene constraints and mapping language terms to code terms. gpt-4o is used here.

Coding. The coding module implements the plan created by the Staging module. It takes several key elements: a history containing the staging plan, environment code, summarized documentation on environment attributes, Grounding outputs, desired function headers, and importantly, a checklist of domain knowledge. In ROSETTA, this includes knowledge on densifying reward, masking staged rewards, and considering problem geometry: all crucial to reward success. The full checklist is in Sec. D. For long-horizon action primitive environments, the Coding module generates target positions, dense position reward, and success conditions for each stage. These are inserted into a task-agnostic template to ensure action space adherence. In short-horizon continuous control, all code is generated. The Coding module uses o1-mini.

Policy Training. ROSETTA results in $V*N$ reward functions, where V is the number of variants and N is the number of end-to-end generations. V is fixed based on the number of verification questions, whereas N is a hyperparameter. We train at most three variants per generation given resource constraints. To select $\pi^{(t)}$ at iteration step t , we take the best policy from each reward variant’s training run and let the preference annotator choose. Consider the set of variants $\mathcal{R}^{(t)} = \text{ROSETTA}(h^{(t)})$. For all $R \in \mathcal{R}^{(t)}$, we take policies $\mathcal{A}_M(R)_{k^*}$ where k^* is the training iteration with the highest success rate; if success rate for all training iterations is 0, we use maximum average accumulated reward. The chosen policy is $\pi^{(t)}$. Since the annotator chose it, its reward function R^* is by definition the one that maximizes $F^{(t)}(\mathcal{A}(R)_{k^*})$. Given the goal of investigating automated reward generation and selection, we choose hyperparameters *a priori* for each environment, but do not tune for any specific reward function. With sufficient resources, systematic hyperparameter tuning can be integrated.

V. EXPERIMENTS

ROSETTA aims to handle natural human preference in a way that is satisfactory to that human. We investigate this through four research questions:

- Q1: Does ROSETTA generate adaptive reward functions given a sequence of human preferences?
- Q2: Can ROSETTA handle diverse, unconstrained human language?
- Q3: Can ROSETTA handle dynamic, unseen preferences, even as they compound over time?
- Q4: Does the proposed evaluation framework offer insights beyond standard training metrics?

A. Experiment Setup

Training and environments. We conduct experiments in two settings. Short-horizon: 7-DoF operational space control, training with proximal policy optimization [40], two task-agnostic environments (SphereAndBins and BallAndTarget) each with ten preference sequences of length four. Long-horizon: hierarchical policy trained with soft actor-critic [12] and primitive skills adapted from MAPLE [33], three task-agnostic environments (ThreeCubes, ObjectsAndBins, ObjectsAndDrawer) each with five preference sequences of length two or three. For both, we use ManiSkill 3 [46] and the Franka Panda [14]. Annotators are sourced from Upwork [47]. Full details in Sec. M0b.

Baselines. We compare ROSETTA to Eureka [31] and Text2Reward [54]. Both use multiple rounds of language feedback to optimize a fixed goal, with the language feedback being purposely written to help shape this reward. We test each method by inputting a human language preference, then having that human select among policy videos from the generated functions. As noted in Sec. III, we consider human evaluation to be the fitness function for all methods. We begin with the original ManiSkill reward, then evaluate every method after a single round of application to test immediate adaptation. We apply the training pipeline described in Sec. IV.

Ablations. We compare to three ablations: 1) ROSETTA-no-grounding, in which we give the original human preference directly to Staging. 2) ROSETTA-no-staging, in which we ground the preference and give it directly to a version of Coding with all mentions of “stage” removed. 3) ROSETTA-no-followup, in which we do not apply any follow-up questions.

Metrics. For alignment, we consider percent preferences where the annotator was more satisfied and average Likert-scale satisfaction score. For semantic match, we consider seven-point Likert scores for each of Grounding, Staging, and Coding. We multiply these to get a Cascading score. For optimizability, we consider the average training success rate and percent of preferences that have a policy with a success rate >50%. Detailed definitions of each metric are in Sec. K.

B. Results

- 1) ROSETTA generates adaptive rewards to sequences of human preferences (Q1): ROSETTA generates semantically

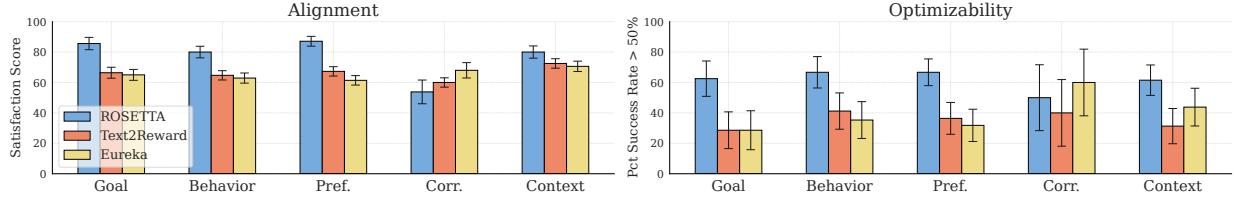


Fig. 3: ROSETTA vs baselines, compared on optimizability and alignment for goal, behavior, preferential, corrective, and context-dependent preferences. ROSETTA outperforms on all preferences except corrective, as expected given Eureka and Text2Reward are built for the corrective setting.

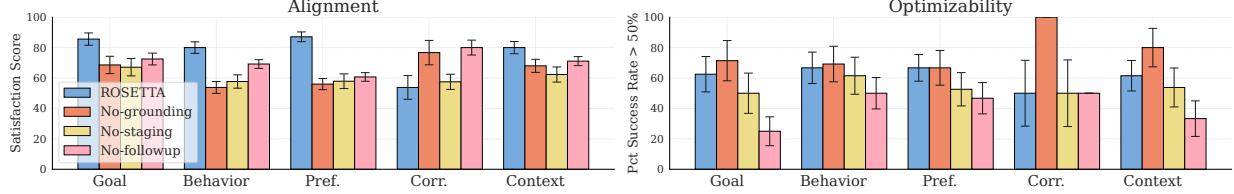


Fig. 4: ROSETTA vs ablations, compared as in Fig 3. ROSETTA outperforms on alignment metrics for all preferences other than corrective. For optimizability, ROSETTA-no-grounding appears superior because ungrounded preferences often result in minimal edits to the prior reward. If it is optimizable, the success rate will be high despite it being misaligned. See Sec. V-B4 for analysis.

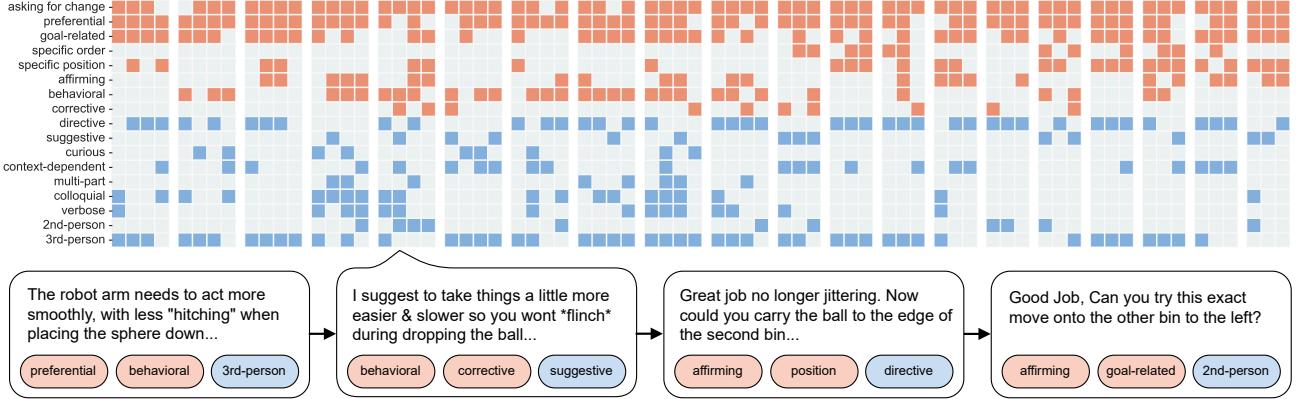


Fig. 5: Visualization of diverse human preferences. Each column is one human preference, and each group of columns is a preference sequence. Colored cells indicate applicable categories: orange for language, blue for content. A full list of preference categories can be found in Sec. K.

matched, optimizable, and aligned reward functions for sequences of human preferences. In Tab. I, we show overall and step-by-step metrics on all environments. ROSETTA improves human satisfaction on 86.0% of all preferences and achieves 79.0% satisfaction score across all preferences. It has even higher success rate and percent success $>50\%$, and similarly successful performance on semantic match; all measured across both short- and long-horizon. Per-interaction step, we see in Tab. I and Tab. II that performance is maintained even as context and changes layer on each other, with at least 80% of preferences resulting in satisfaction and at least 75% satisfaction score in each step. Though changing goals and highly context-dependent preferences provide natural challenges, ROSETTA adapts to these effectively. There is some degradation in training metrics and degree of satisfaction, often caused either by the preference annotator doubling down on difficult preferences or hallucinations from prior steps contaminating the current prompt. The latter is a key failure

of prompting with environment code that includes the prior reward function to get natural grounding (examples in Sec. C1).

a) Comparing to baselines: We see in Fig. 3 that ROSETTA outperforms Eureka and Text2Reward, particularly when the preference changes task requirements. We compare on preferences that are corrective (give corrections on the same task requirements), preferential (add/change task requirements), goal-related (address success definition), and behavioral (address other parts of reward landscape). While the baselines are similar on corrective preferences, ROSETTA outperforms significantly on preferential, as well as outperforms on goal-related and behavioral which are also preferential.

2) ROSETTA extracts signal from diverse, unconstrained language (Q2): Human can communicate preferences with diverse language categories as shown in Fig. 5. ROSETTA has consistent performance across language features that are difficult for foundation models, such as *specific positions* and *context-dependent*, as shown in Figs. 7 and 8. The *specific*



Fig. 6: Example real robot results. The first element in each color column represents a preference given to the policy trained on the original task. The second element represents another iteration of preference given on its parent. We see that simulation-trained policies transfer to real effectively.

Iter.	Succ. Rate	% Succ. >50	More Sat.	Sat. Score
1	94.6	95.2	90.0	90.0
2	89.4	90.0	80.0	75.6
3	94.4	100.0	80.0	76.9
4	78.1	75.0	89.5	78.9

TABLE I: Breakdown of optimizability and alignment across iterations. Metrics are as described in Sec. V-A.

positions category has complex and often evolving position descriptions. These are challenging for foundation models given the lack of spatial reasoning [28]. The *context-dependent* category includes preferences that require prior context, e.g. a sequence like “red on top” then “other one actually.” Without context, the second preference would be impossible to interpret even for a human. ROSETTA generates productive reward functions even in these challenging cases, achieving 60% success rate and 92% satisfaction score on specific position preference, and 73% success rate and 76% satisfaction score on context-dependent preference. Fig. 5 shows the language diversity of collected preferences. ROSETTA’s ability to handle unconstrained language comes from the Preference Grounding and Staging modules that interpret the language. In Fig. 4, ROSETTA-no-grounding suffers on alignment for context-dependent preferences where environment code is insufficient, going from 80% satisfaction score and 84.6% more satisfied to 68% and 70%. ROSETTA-no-staging suffers in general, performing 22.2% worse on satisfaction score overall.

3) ROSETTA can handle dynamic, unseen preferences that compound over time.: Besides diverse language features, human preferences also contain diverse contents as in Fig. 5. ROSETTA maintains performance across content features based on Fig. 7. Policies reach specific positions (“right edge of left bin”) and orientations (“give it a quarter-turn”), and adapt to behavior preferences (“smoother movement”, “go slower, that’s stressful to watch”); more examples in Sec. B. As in comparison to baselines, we see ROSETTA’s superior ability to handle changing task requirements. Tab. 4 shows that ROSETTA outperforms ablations on *goal-related*, *behavioral*, and *preferential* content. ROSETTA-no-followup matches performance only in *corrective* cases where the domain-knowledge follow-ups are distracting rather than helpful. Tab. I demonstrates that ROSETTA’s performance shows only limited degradation, staying above 75% on all metrics. The strength comes from both o1-mini’s coding and reasoning capabilities and ROSETTA’s

domain knowledge. Fig. 7 demonstrates ROSETTA’s content failure modes. Details are in Sec. 0b.

4) Effectiveness of the Evaluation Framework (Q4) : The proposed evaluation framework investigates performance more deeply than standard metrics alone. ROSETTA is performant on all metrics as shown in Tab. II, but overlap is not a given: 73% of human-selected policies have $\geq 50\%$ success rate, and only 66% have the highest success rate across all options. Optimizability metrics retain practical value in assessing whether ROSETTA is technically reliable: high success rates indicate behavior that is expected from the reward function.

Low-alignment high-optimizability rewards appear when the reward code effectively induces its own success condition, but the success condition itself does not match the preference: a semantic hallucination. A common example: ROSETTA is given a preference with nonstandard phrasing and mostly ignores it, outputting a barely-edited version of the previous reward function. The result is a good success rate but a behavior that does not reflect the input. This is part of the reason the ROSETTA-no-grounding ablation, in which Staging and Coding receive more nonstandard phrasing, has high optimizability but significantly lower alignment than ROSETTA. It does match ROSETTA’s alignment on corrective preferences, where not changing the success condition is ideal. **High-alignment low-optimizability** rewards demonstrate deeper challenges. We find that without alignment, we wouldn’t know the annotator’s true opinion; but without optimizability we don’t know the reasons for failure. For example, given preference to “push the ball on the table next to the bin” rather than picking and placing, the human-selected rollout shows a gentle, ineffectual push toward the bin with a success rate of 0; the high-success rate policies do pick and place. **Key misalignments:** for the annotator, the push is more important than the position, but this is unclear from the language. Second, ROSETTA set a specific target point because this is typically more optimizable than a target region, but here that point was difficult to push to. Third, the reward function did encourage a closed gripper, but the success boost outweighed the opening penalty.

5) Real robot experiments: We take a sim-to-real approach for real robot experiments. We test on four two-iteration preference chains in the ThreeCubes long-horizon task-agnostic environment for which policies have been trained in simulation. We track positions of the cubes from a single RGB image using FoundationPose [50], then populate the state dictionary required

for our long-horizon action primitive setting. The average first iteration success rate is 72.5%; the average second iteration success rate is 80.0%. Examples are shown in Fig. 6. We observe no sim-to-real gap from the policy.

VI. CONCLUSION AND LIMITATION

We aimed to investigate how reward signals can be extracted from unconstrained, diverse, and dynamic human language to train embodied AI agents. We present ROSETTA which takes in such language, extracts desired task content, and generates useful reward functions even when that content changes and contradicts prior content. One key limitation is the expert evaluation for Semantic Match metrics. Analytic/learned metrics may be cheaper and more objective.

REFERENCES

- [1] Michael Ahn, Anthony Brohan, Noah Brown, Yevgen Chebotar, Omar Cortes, Byron David, Chelsea Finn, Chuyuan Fu, Keerthana Gopalakrishnan, Karol Hausman, Alex Herzog, Daniel Ho, Jasmine Hsu, Julian Ibarz, Brian Ichter, Alex Irpan, Eric Jang, Rosario Jauregui Ruano, Kyle Jeffrey, Sally Jesmonth, Nikhil J Joshi, Ryan Julian, Dmitry Kalashnikov, Yuheng Kuang, Kuang-Huei Lee, Sergey Levine, Yao Lu, Linda Luu, Carolina Parada, Peter Pastor, Jornell Quiambao, Kanishka Rao, Jarek Rettinghouse, Diego Reyes, Pierre Sermanet, Nicolas Sievers, Clayton Tan, Alexander Toshev, Vincent Vanhoucke, Fei Xia, Ted Xiao, Peng Xu, Sichun Xu, Mengyuan Yan, and Andy Zeng. Do as i can, not as i say: Grounding language in robotic affordances, 2022. URL <https://arxiv.org/abs/2204.01691>.
- [2] Saurabh Arora and Prashant Doshi. A survey of inverse reinforcement learning: Challenges, methods and progress, 2020. URL <https://arxiv.org/abs/1806.06877>.
- [3] Andreea Bobu, Andi Peng, Pulkit Agrawal, Julie A. Shah, and Anca D. Dragan. Aligning human and robot representations. In *HRI*, pages 42–54, 2024. URL <https://doi.org/10.1145/3610977.3634987>.
- [4] Rishi Bommasani, Drew A. Hudson, Ehsan Adeli, Russ Altman, Simran Arora, Sydney von Arx, Michael S. Bernstein, Jeannette Bohg, Antoine Bosselut, Emma Brunskill, Erik Brynjolfsson, Shyamal Buch, Dallas Card, Rodrigo Castellon, Niladri Chatterji, Annie Chen, Kathleen Creel, Jared Quincy Davis, Dora Demszky, Chris Donahue, Moussa Doumbouya, Esin Durmus, Stefano Ermon, John Etchemendy, Kawin Ethayarajh, Li Fei-Fei, Chelsea Finn, Trevor Gale, Lauren Gillespie, Karan Goel, Noah Goodman, Shelby Grossman, Neel Guha, Tatsunori Hashimoto, Peter Henderson, John Hewitt, Daniel E. Ho, Jenny Hong, Kyle Hsu, Jing Huang, Thomas Icard, Saahil Jain, Dan Jurafsky, Pratyusha Kalluri, Siddharth Karamcheti, Geoff Keeling, Fereshte Khani, Omar Khattab, Pang Wei Koh, Mark Krass, Ranjay Krishna, Rohith Kuditipudi, Ananya Kumar, Faisal Ladha, Mina Lee, Tony Lee, Jure Leskovec, Isabelle Levent, Xiang Lisa Li, Xuechen Li, Tengyu Ma, Ali Malik, Christopher D. Manning, Suvir Mirchandani, Eric Mitchell, Zanele Munyikwa, Suraj Nair, Avanika Narayan, Deepak Narayanan, Ben Newman, Allen Nie, Juan Carlos Niebles, Hamed Nilforoshan, Julian Nyarko, Giray Ogut, Laurel Orr, Isabel Papadimitriou, Joon Sung Park, Chris Piech, Eva Portelance, Christopher Potts, Aditi Raghunathan, Rob Reich, Hongyu Ren, Frieda Rong, Yusuf Roohani, Camilo Ruiz, Jack Ryan, Christopher Ré, Dorsa Sadigh, Shiori Sagawa, Keshav Santhanam, Andy Shih, Krishnan Srinivasan, Alex Tamkin, Rohan Taori, Armin W. Thomas, Florian Tramèr, Rose E. Wang, William Wang, Bohan Wu, Jiajun Wu, Yuhuai Wu, Sang Michael Xie, Michihiro Yasunaga, Jiaxuan You, Matei Zaharia, Michael Zhang, Tianyi Zhang, Xikun Zhang, Yuhui Zhang, Lucia Zheng, Kaitlyn Zhou, and Percy Liang. On the opportunities and risks of foundation models, 2022. URL <https://arxiv.org/abs/2108.07258>.
- [5] Annie S. Chen, Suraj Nair, and Chelsea Finn. Learning generalizable robotic reward functions from "in-the-wild" human videos, 2021. URL <https://arxiv.org/abs/2103.16817>.
- [6] Yongchao Chen, Jacob Arkin, Yang Zhang, Nicholas A. Roy, and Chuchu Fan. Autotamp: Autoregressive task and motion planning with llms as translators and checkers. *ArXiv*, abs/2306.06531, 2023. URL <https://api.semanticscholar.org/CorpusID:259138811>.
- [7] Yung-Sung Chuang, Linlu Qiu, Cheng-Yu Hsieh, Ranjay Krishna, Yoon Kim, and James R. Glass. Lookback lens: Detecting and mitigating contextual hallucinations in large language models using only attention maps. In Yaser Al-Onaizan, Mohit Bansal, and Yun-Nung Chen, editors, *Proceedings of the 2024 Conference on Empirical Methods in Natural Language Processing*, pages 1419–1436, Miami, Florida, USA, November 2024. Association for Computational Linguistics. doi: 10.18653/v1/2024.emnlp-main.84. URL <https://aclanthology.org/2024.emnlp-main.84/>.
- [8] Vincent Conitzer, Rachel Freedman, Jobst Heitzig, Wesley H. Holliday, Bob M. Jacobs, Nathan Lambert, Milan Mossé, Eric Pacuit, Stuart Russell, Hailey Schoelkopf, Emanuel Tewolde, and William S. Zwicker. Position: Social choice should guide AI alignment in dealing with diverse human feedback. In *Forty-first International Conference on Machine Learning*, 2024. URL <https://openreview.net/forum?id=w1d9DOGymR>.
- [9] Yuchen Cui, Siddharth Karamcheti, Raj Palletti, Nidhya Shivakumar, Percy Liang, and Dorsa Sadigh. No, to the right: Online language corrections for robotic manipulation via shared autonomy. In *Proceedings of the 2023 ACM/IEEE International Conference on Human-Robot Interaction*, HRI '23. ACM, March 2023. doi: 10.1145/3568162.3578623. URL <http://dx.doi.org/10.1145/3568162.3578623>.
- [10] Fernando Delgado, Stephen Yang, Michael Madaio, and Qian Yang. The participatory turn in ai design: Theoretical foundations and the current state of practice, 2023. URL <https://arxiv.org/abs/2310.00907>.

- [11] Yuqing Du, Ksenia Konyushkova, Misha Denil, Akhil Raju, Jessica Landon, Felix Hill, Nando de Freitas, and Serkan Cabi. Vision-language models as success detectors, 2023. URL <https://arxiv.org/abs/2303.07280>.
- [12] Tuomas Haarnoja, Aurick Zhou, Pieter Abbeel, and Sergey Levine. Soft actor-critic: Off-policy maximum entropy deep reinforcement learning with a stochastic actor, 2018. URL <https://openreview.net/forum?id=HJjvx1-Cb>.
- [13] Tuomas Haarnoja, Aurick Zhou, Kristian Hartikainen, George Tucker, Sehoon Ha, Jie Tan, Vikash Kumar, Henry Zhu, Abhishek Gupta, Pieter Abbeel, et al. Soft actor-critic algorithms and applications. *arXiv preprint arXiv:1812.05905*, 2018.
- [14] Sami Haddadin, Sven Parusel, Lars Johannsmeier, Saskia Golz, Simon Gabl, Florian Walch, Mohamadreza Sabaghian, Christoph Jähne, Lukas Hausperger, and Simon Haddadin. The franka emika robot: A reference platform for robotics research and education. *IEEE Robotics & Automation Magazine*, 29(2):46–64, 2022. doi: 10.1109/MRA.2021.3138382.
- [15] Rishi Hazra, Alkis Sygkounas, Andreas Persson, Amy Loutfi, and Pedro Zuidberg Dos Martires. Revolve: Reward evolution with large language models using human feedback, 2024. URL <https://arxiv.org/abs/2406.01309>.
- [16] Wenlong Huang, Pieter Abbeel, Deepak Pathak, and Igor Mordatch. Language models as zero-shot planners: Extracting actionable knowledge for embodied agents. *arXiv preprint arXiv:2201.07207*, 2022.
- [17] Wenlong Huang, F. Xia, Ted Xiao, Harris Chan, Jacky Liang, Peter R. Florence, Andy Zeng, Jonathan Tompson, Igor Mordatch, Yevgen Chebotar, Pierre Sermanet, Noah Brown, Tomas Jackson, Linda Luu, Sergey Levine, Karol Hausman, and Brian Ichter. Inner monologue: Embodied reasoning through planning with language models. In *Conference on Robot Learning*, 2022. URL <https://api.semanticscholar.org/CorpusID:250451569>.
- [18] Wenlong Huang, Chen Wang, Ruohan Zhang, Yunzhu Li, Jiajun Wu, and Li Fei-Fei. Voxposer: Composable 3d value maps for robotic manipulation with language models, 2023. URL <https://arxiv.org/abs/2307.05973>.
- [19] Minyoung Hwang, Luca Weihs, Chanwoo Park, Kimin Lee, Aniruddha Kembhavi, and Kiana Ehsani. Promptable behaviors: Personalizing multi-objective rewards from human preferences, 2023. URL <https://arxiv.org/abs/2312.09337>.
- [20] Michael Hyman and Jeremy Sierra. Open- versus closed-ended survey questions. *NMSU Business Outlook*, 14, 02 2016.
- [21] Jan Leike, David Krueger, Tom Everitt, Miljan Martic, Vishal Maini, and Shane Legg. Scalable agent alignment via reward modeling: a research direction. *CoRR*, abs/1811.07871, 2018. URL <http://arxiv.org/abs/1811.07871>.
- [22] Boyi Li, Philipp Wu, Pieter Abbeel, and Jitendra Malik. Interactive task planning with language models, 2023. URL <https://arxiv.org/abs/2310.10645>.
- [23] Chengshu Li, Ruohan Zhang, Josiah Wong, Cem Gokmen, Sanjana Srivastava, Roberto Martín-Martín, Chen Wang, Gabrael Levine, Michael Lingelbach, Jiankai Sun, Mona Anvari, Minjune Hwang, Manasi Sharma, Arman Aydin, Dhruva Bansal, Samuel Hunter, Kyu-Young Kim, Alan Lou, Caleb R Matthews, Ivan Villa-Renteria, Jerry Huayang Tang, Claire Tang, Fei Xia, Silvio Savarese, Hyowon Gweon, Karen Liu, Jiajun Wu, and Li Fei-Fei. BEHAVIOR-1k: A benchmark for embodied AI with 1,000 everyday activities and realistic simulation. In *6th Annual Conference on Robot Learning*, 2022. URL https://openreview.net/forum?id=_8Dole8G3t.
- [24] Manling Li, Shiyu Zhao, Qineng Wang, Kangrui Wang, Yu Zhou, Sanjana Srivastava, Cem Gokmen, Tony Lee, Li Erran Li, Ruohan Zhang, et al. Embodied agent interface: Benchmarking llms for embodied decision making. In *NeurIPS 2024*, 2024.
- [25] Zhaoyi Li, Kelin Yu, Shuo Cheng, and Danfei Xu. LEAGUE++: Empowering continual robot learning through guided skill acquisition with large language models. In *ICLR 2024 Workshop on Large Language Model (LLM) Agents*, 2024.
- [26] Jacky Liang, Wenlong Huang, Fei Xia, Peng Xu, Karol Hausman, Brian Ichter, Pete Florence, and Andy Zeng. Code as policies: Language model programs for embodied control. In *arXiv preprint arXiv:2209.07753*, 2022.
- [27] Jacky Liang, Fei Xia, Wenhao Yu, Andy Zeng, Montserrat Gonzalez Arenas, Maria Attarian, Maria Bauza, Matthew Bennice, Alex Bewley, Adil Dostmohamed, Chuyuan Kelly Fu, Nimrod Gileadi, Marissa Giustina, Keerthana Gopalakrishnan, Leonard Hasen clever, Jan Humplik, Jasmine Hsu, Nikhil Joshi, Ben Jyenis, Chase Kew, Sean Kirmani, Tsang-Wei Edward Lee, Kuang-Huei Lee, Assaf Hurwitz Michael, Joss Moore, Ken Oslund, Dushyant Rao, Allen Ren, Baruch Tabanpour, Quan Vuong, Ayzaan Wahid, Ted Xiao, Ying Xu, Vincent Zhuang, Peng Xu, Erik Frey, Ken Caluwaerts, Tingnan Zhang, Brian Ichter, Jonathan Tompson, Leila Takayama, Vincent Vanhoucke, Izhak Shafran, Maja Mataric, Dorsa Sadigh, Nicolas Heess, Kanishka Rao, Nik Stewart, Jie Tan, and Carolina Parada. Learning to learn faster from human feedback with language model predictive control. 2024. URL <https://arxiv.org/abs/2402.11450>.
- [28] Yuan-Hong Liao, Rafid Mahmood, Sanja Fidler, and David Acuna. Reasoning paths with reference objects elicit quantitative spatial reasoning in large vision-language models. In Yaser Al-Onaizan, Mohit Bansal, and Yun-Nung Chen, editors, *Proceedings of the 2024 Conference on Empirical Methods in Natural Language Processing*, pages 17028–17047, Miami, Florida, USA, November 2024. Association for Computational Linguistics. doi: 10.18653/v1/2024.emnlp-main.947. URL <https://aclanthology.org/2024.emnlp-main.947>.
- [29] Huihan Liu, Alice Chen, Yuke Zhu, Adith Swaminathan, Andrey Kolobov, and Ching-An Cheng. Interactive robot learning from verbal correction, 2023. URL <https://arxiv.org/abs/2310.10645>.

org/abs/2310.17555.

- [30] Yecheng Jason Ma, Joey Hejna, Ayzaan Wahid, Chuyuan Fu, Dhruv Shah, Jacky Liang, Zhuo Xu, Sean Kirmani, Peng Xu, Danny Driess, Ted Xiao, Jonathan Tompson, Osbert Bastani, Dinesh Jayaraman, Wenhao Yu, Tingnan Zhang, Dorsa Sadigh, and Fei Xia. Vision language models are in-context value learners, 2024. URL <https://arxiv.org/abs/2411.04549>.
- [31] Yecheng Jason Ma, William Liang, Guanzhi Wang, De-An Huang, Osbert Bastani, Dinesh Jayaraman, Yuke Zhu, Linxi Fan, and Anima Anandkumar. Eureka: Human-level reward design via coding large language models. In *The Twelfth International Conference on Learning Representations*, 2024. URL <https://openreview.net/forum?id=IEduRUO55F>.
- [32] Soroush Nasiriany, Huihan Liu, and Yuke Zhu. Augmenting reinforcement learning with behavior primitives for diverse manipulation tasks. In *2022 International Conference on Robotics and Automation (ICRA)*, pages 7477–7484. IEEE, 2022.
- [33] Soroush Nasiriany, Huihan Liu, and Yuke Zhu. Augmenting reinforcement learning with behavior primitives for diverse manipulation tasks. In *IEEE International Conference on Robotics and Automation (ICRA)*, 2022.
- [34] OpenAI, :, Aaron Hurst, Adam Lerer, Adam P. Goucher, Adam Perelman, Aditya Ramesh, Aidan Clark, AJ Ostrow, Akila Welihinda, Alan Hayes, Alec Radford, Aleksander Mądry, Alex Baker-Whitcomb, Alex Beutel, Alex Borzunov, Alex Carney, Alex Chow, Alex Kirillov, Alex Nichol, Alex Paino, Alex Renzin, Alex Tachard Passos, Alexander Kirillov, Alexi Christakis, Alexis Conneau, Ali Kamali, Allan Jabri, Allison Moyer, Allison Tam, Amadou Crookes, Amin Tootoochian, Amin Tootoonchian, Ananya Kumar, Andrea Vallone, Andrej Karpathy, Andrew Bernstein, Andrew Cann, Andrew Codispoti, Andrew Galu, Andrew Kondrich, Andrew Tulloch, Andrey Mishchenko, Angela Baek, Angela Jiang, Antoine Pelisse, Antonia Woodford, Anuj Gosalia, Arka Dhar, Ashley Pantuliano, Avi Nayak, Avital Oliver, Barret Zoph, Behrooz Ghorbani, Ben Leimberger, Ben Rossen, Ben Sokolowsky, Ben Wang, Benjamin Zweig, Beth Hoover, Blake Samic, Bob McGrew, Bobby Spero, Bogo Giertler, Bowen Cheng, Brad Lightcap, Brandon Walkin, Brendan Quinn, Brian Guaraci, Brian Hsu, Bright Kellogg, Brydon Eastman, Camillo Lugaresi, Carroll Wainwright, Cary Bassin, Cary Hudson, Casey Chu, Chad Nelson, Chak Li, Chan Jun Shern, Channing Conger, Charlotte Barette, Chelsea Voss, Chen Ding, Cheng Lu, Chong Zhang, Chris Beaumont, Chris Hallacy, Chris Koch, Christian Gibson, Christina Kim, Christine Choi, Christine McLeavey, Christopher Hesse, Claudia Fischer, Clemens Winter, Coley Czarnecki, Colin Jarvis, Colin Wei, Constantin Koumouzelis, Dane Sherburn, Daniel Kappler, Daniel Levin, Daniel Levy, David Carr, David Farhi, David Mely, David Robinson, David Sasaki, Denny Jin, Dev Valladares, Dimitris Tsipras, Doug Li, Duc Phong Nguyen, Duncan Findlay, Edede Oiwoh, Edmund Wong, Ehsan Asdar, Elizabeth Proehl, Elizabeth Yang, Eric Antonow, Eric Kramer, Eric Peterson, Eric Sigler, Eric Wallace, Eugene Brevdo, Evan Mays, Farzad Khorasani, Felipe Petroski Such, Filippo Ras, Francis Zhang, Fred von Lohmann, Freddie Sulit, Gabriel Goh, Gene Oden, Geoff Salmon, Giulio Starace, Greg Brockman, Hadi Salman, Haiming Bao, Haitang Hu, Hannah Wong, Haoyu Wang, Heather Schmidt, Heather Whitney, Heewoo Jun, Hendrik Kirchner, Henrique Ponde de Oliveira Pinto, Hongyu Ren, Huiwen Chang, Hyung Won Chung, Ian Kivlichan, Ian O’Connell, Ian O’Connell, Ian Osband, Ian Silber, Ian Sohl, Ibrahim Okuyucu, Ikai Lan, Ilya Kostrikov, Ilya Sutskever, Ingmar Kanitscheider, Ishaan Gulrajani, Jacob Coxon, Jacob Menick, Jakub Pachocki, James Aung, James Betker, James Crooks, James Lennon, Jamie Kiros, Jan Leike, Jane Park, Jason Kwon, Jason Phang, Jason Teplitz, Jason Wei, Jason Wolfe, Jay Chen, Jeff Harris, Jenia Varavva, Jessica Gan Lee, Jessica Shieh, Ji Lin, Jiahui Yu, Jiayi Weng, Jie Tang, Jieqi Yu, Joanne Jang, Joaquin Quinonero Candela, Joe Beutler, Joe Landers, Joel Parish, Johannes Heidecke, John Schulman, Jonathan Lachman, Jonathan McKay, Jonathan Uesato, Jonathan Ward, Jong Wook Kim, Joost Huizinga, Jordan Sitkin, Jos Kraaijeveld, Josh Gross, Josh Kaplan, Josh Snyder, Joshua Achiam, Joy Jiao, Joyce Lee, Juntang Zhuang, Justyn Harriman, Kai Fricke, Kai Hayashi, Karan Singh, Katy Shi, Kavin Karthik, Kayla Wood, Kendra Rimbach, Kenny Hsu, Kenny Nguyen, Keren Gu-Lemberg, Kevin Button, Kevin Liu, Kiel Howe, Krithika Muthukumar, Kyle Luther, Lama Ahmad, Larry Kai, Lauren Itow, Lauren Workman, Leher Pathak, Leo Chen, Li Jing, Lia Guy, Liam Fedus, Liang Zhou, Lien Mamitsuka, Lilian Weng, Lindsay McCallum, Lindsey Held, Long Ouyang, Louis Feuvrier, Lu Zhang, Lukas Kondraciuk, Lukasz Kaiser, Luke Hewitt, Luke Metz, Lyric Doshi, Mada Aflak, Maddie Simens, Madeleine Boyd, Madeleine Thompson, Marat Dukhan, Mark Chen, Mark Gray, Mark Hudnall, Marvin Zhang, Marwan Aljubeh, Mateusz Litwin, Matthew Zeng, Max Johnson, Maya Shetty, Mayank Gupta, Meghan Shah, Mehmet Yatbaz, Meng Jia Yang, Mengchao Zhong, Mia Glaese, Mianna Chen, Michael Janner, Michael Lampe, Michael Petrov, Michael Wu, Michele Wang, Michelle Fradin, Michelle Pokrass, Miguel Castro, Miguel Oom Temudo de Castro, Mikhail Pavlov, Miles Brundage, Miles Wang, Minal Khan, Mira Murati, Mo Bavarian, Molly Lin, Murat Yesildal, Nacho Soto, Natalia Gimelshein, Natalie Cone, Natalie Staudacher, Natalie Summers, Natan LaFontaine, Neil Chowdhury, Nick Ryder, Nick Stathas, Nick Turley, Nik Tezak, Niko Felix, Nithanth Kudige, Nitish Keskar, Noah Deutsch, Noel Bundick, Nora Puckett, Ofir Nachum, Ola Okelola, Oleg Boiko, Oleg Murk, Oliver Jaffe, Olivia Watkins, Olivier Godement, Owen Campbell-Moore, Patrick Chao, Paul McMillan, Pavel Belov, Peng Su, Peter Bak, Peter Bakkum, Peter Deng, Peter Dolan, Peter Hoeschele, Peter Welinder, Phil Tillet, Philip Pronin,

Philippe Tillet, Prafulla Dhariwal, Qiming Yuan, Rachel Dias, Rachel Lim, Rahul Arora, Rajan Troll, Randall Lin, Rapha Gontijo Lopes, Raul Puri, Reah Miyara, Reimar Leike, Renaud Gaubert, Reza Zamani, Ricky Wang, Rob Donnelly, Rob Honsby, Rocky Smith, Rohan Sahai, Rohit Ramchandani, Romain Huet, Rory Carmichael, Rowan Zellers, Roy Chen, Ruby Chen, Ruslan Nigmatullin, Ryan Cheu, Saachi Jain, Sam Altman, Sam Schoenholz, Sam Toizer, Samuel Miserendino, Sandhini Agarwal, Sara Culver, Scott Ethersmith, Scott Gray, Sean Grove, Sean Metzger, Shamez Hermani, Shantanu Jain, Shengjia Zhao, Sherwin Wu, Shino Jomoto, Shirong Wu, Shuaiqi Xia, Sonia Phene, Spencer Papay, Srinivas Narayanan, Steve Coffey, Steve Lee, Stewart Hall, Suchir Balaji, Tal Broda, Tal Stramer, Tao Xu, Tarun Gogineni, Taya Christianson, Ted Sanders, Tejal Patwardhan, Thomas Cunningham, Thomas Degry, Thomas Dimson, Thomas Raoux, Thomas Shadwell, Tianhao Zheng, Todd Underwood, Todor Markov, Toki Sherbakov, Tom Rubin, Tom Stasi, Tomer Kaftan, Tristan Heywood, Troy Peterson, Tyce Walters, Tyna Eloundou, Valerie Qi, Veit Moeller, Vinnie Monaco, Vishal Kuo, Vlad Fomenko, Wayne Chang, Weiyi Zheng, Wenda Zhou, Wesam Manassra, Will Sheu, Wojciech Zaremba, Yash Patil, Yilei Qian, Yongjik Kim, Youlong Cheng, Yu Zhang, Yuchen He, Yuchen Zhang, Yujia Jin, Yunxing Dai, and Yury Malkov. Gpt-4o system card, 2024. URL <https://arxiv.org/abs/2410.21276>.

- [35] OpenAI, :, Aaron Jaech, Adam Kalai, Adam Lerer, Adam Richardson, Ahmed El-Kishky, Aiden Low, Alec Helyar, Aleksander Madry, Alex Beutel, Alex Carney, Alex Iftimie, Alex Karpenko, Alex Tachard Passos, Alexander Neitz, Alexander Prokofiev, Alexander Wei, Allison Tam, Ally Bennett, Ananya Kumar, Andre Saraiva, Andrea Vallone, Andrew Duberstein, Andrew Kondrich, Andrey Mishchenko, Andy Applebaum, Angela Jiang, Ashvin Nair, Barret Zoph, Behrooz Ghorbani, Ben Rossen, Benjamin Sokolowsky, Boaz Barak, Bob McGrew, Borys Minaev, Botao Hao, Bowen Baker, Brandon Houghton, Brandon McKinzie, Brydon Eastman, Camillo Lugaresi, Cary Bassin, Cary Hudson, Chak Ming Li, Charles de Bourcy, Chelsea Voss, Chen Shen, Chong Zhang, Chris Koch, Chris Orsinger, Christopher Hesse, Claudia Fischer, Clive Chan, Dan Roberts, Daniel Kappler, Daniel Levy, Daniel Selsam, David Dohan, David Farhi, David Mely, David Robinson, Dimitris Tsipras, Doug Li, Dragos Oprica, Eben Freeman, Eddie Zhang, Edmund Wong, Elizabeth Proehl, Enoch Cheung, Eric Mitchell, Eric Wallace, Erik Ritter, Evan Mays, Fan Wang, Felipe Petroski Such, Filippo Raso, Florencia Leoni, Foivos Tsimpourlas, Francis Song, Fred von Lohmann, Freddie Sulit, Geoff Salmon, Giambattista Parascandolo, Gildas Chabot, Grace Zhao, Greg Brockman, Guillaume Leclerc, Hadi Salman, Haiming Bao, Hao Sheng, Hart Andrin, Hessam Bagherinezhad, Hongyu Ren, Hunter Lightman, Hyung Won Chung, Ian Kivlichan, Ian O'Connell, Ian Osband, Ignasi Clavera Gilaberte, Ilge Akkaya, Ilya Kostrikov, Ilya Sutskever, Irina Kofman, Jakub Pachocki, James Lennon, Jason Wei, Jean Harb, Jerry Twore, Jiacheng Feng, Jiahui Yu, Jiayi Weng, Jie Tang, Jieqi Yu, Joaquin Quiñonero Candela, Joe Palermo, Joel Parish, Johannes Heidecke, John Hallman, John Rizzo, Jonathan Gordon, Jonathan Uesato, Jonathan Ward, Joost Huizinga, Julie Wang, Kai Chen, Kai Xiao, Karan Singhal, Karina Nguyen, Karl Cobbe, Katy Shi, Kayla Wood, Kendra Rimbach, Keren Gu-Lemberg, Kevin Liu, Kevin Lu, Kevin Stone, Kevin Yu, Lama Ahmad, Lauren Yang, Leo Liu, Leon Maksin, Leyton Ho, Liam Fedus, Lilian Weng, Linden Li, Lindsay McCallum, Lindsey Held, Lorenz Kuhn, Lukas Kondraciuk, Lukasz Kaiser, Luke Metz, Madelaine Boyd, Maja Trebacz, Manas Joglekar, Mark Chen, Marko Tintor, Mason Meyer, Matt Jones, Matt Kaufer, Max Schwarzer, Meghan Shah, Mehmet Yatbaz, Melody Y. Guan, Mengyuan Xu, Mengyuan Yan, Mia Glaese, Mianna Chen, Michael Lampe, Michael Malek, Michele Wang, Michelle Fradin, Mike McClay, Mikhail Pavlov, Miles Wang, Mingxuan Wang, Mira Murati, Mo Bavarian, Mostafa Rohaninejad, Nat McAleese, Neil Chowdhury, Neil Chowdhury, Nick Ryder, Nikolas Tezak, Noam Brown, Ofir Nachum, Oleg Boiko, Oleg Murk, Olivia Watkins, Patrick Chao, Paul Ashbourne, Pavel Izmailov, Peter Zhokhov, Rachel Dias, Rahul Arora, Randall Lin, Rapha Gontijo Lopes, Raz Gaon, Reah Miyara, Reimar Leike, Renny Hwang, Rhythm Garg, Robin Brown, Roshan James, Rui Shu, Ryan Cheu, Ryan Greene, Saachi Jain, Sam Altman, Sam Toizer, Sam Toyer, Samuel Miserendino, Sandhini Agarwal, Santiago Hernandez, Sasha Baker, Scott McKinney, Scottie Yan, Shengjia Zhao, Shengli Hu, Shibani Santurkar, Shraman Ray Chaudhuri, Shuyuan Zhang, Siyuan Fu, Spencer Papay, Steph Lin, Suchir Balaji, Suvansh Sanjeev, Szymon Sidor, Tal Broda, Aidan Clark, Tao Wang, Taylor Gordon, Ted Sanders, Tejal Patwardhan, Thibault Sottiaux, Thomas Degry, Thomas Dimson, Tianhao Zheng, Timur Garipov, Tom Stasi, Trapit Bansal, Trevor Creech, Troy Peterson, Tyna Eloundou, Valerie Qi, Vineet Kosaraju, Vinnie Monaco, Vitchyr Pong, Vlad Fomenko, Weiyi Zheng, Wenda Zhou, Wes McCabe, Wojciech Zaremba, Yann Dubois, Yinghai Lu, Yining Chen, Young Cha, Yu Bai, Yuchen He, Yuchen Zhang, Yunyun Wang, Zheng Shao, and Zhuohan Li. Openai o1 system card, 2024. URL <https://arxiv.org/abs/2412.16720>.
- [36] Liangming Pan, Michael Saxon, Wenda Xu, Deepak Nathani, Xinyi Wang, and William Yang Wang. Automatically correcting large language models: Surveying the landscape of diverse automated correction strategies. *Transactions of the Association for Computational Linguistics*, 12:484–506, 2024. doi: 10.1162/tacl_a_00660. URL <https://aclanthology.org/2024.tacl-1.27/>.
- [37] Juan Rocamonde, Victoriano Montesinos, Elvis Nava, Ethan Perez, and David Lindner. Vision-language models are zero-shot reward models for reinforcement learning, 2024. URL <https://arxiv.org/abs/2310.12921>.

- [38] Domenic Rosati, Robie Gonzales, Jinkun Chen, Xuemin Yu, Melis Erkan, Yahya Kayani, Satya Deepika Chavatapalli, Frank Rudzicz, and Hassan Sajjad. Long-form evaluation of model editing, 2024. URL <https://arxiv.org/abs/2402.09394>.
- [39] Vishnu Sarukkai, Brennan Shacklett, Zander Majercik, Kush Bhatia, Christopher Ré, and Kayvon Fatahalian. Automated rewards via llm-generated progress functions, 2024. URL <https://arxiv.org/abs/2410.09187>.
- [40] John Schulman, Filip Wolski, Prafulla Dhariwal, Alec Radford, and Oleg Klimov. Proximal policy optimization algorithms, 2017. URL <https://arxiv.org/abs/1707.06347>.
- [41] Lucy Xiaoyang Shi, Zheyuan Hu, Tony Z Zhao, Archit Sharma, Karl Pertsch, Jianlan Luo, Sergey Levine, and Chelsea Finn. Yell at your robot: Improving on-the-fly from language corrections. *arXiv preprint arXiv:2403.12910*, 2024.
- [42] Lucy Xiaoyang Shi, Brian Ichter, Michael Equi, Liyiming Ke, Karl Pertsch, Quan Vuong, James Tanner, Anna Walling, Haohuan Wang, Niccolo Fusai, Adrian Li-Bell, Danny Driess, Lachy Groom, Sergey Levine, and Chelsea Finn. Hi robot: Open-ended instruction following with hierarchical vision-language-action models. *arXiv preprint arXiv:2502.19417*, 2025.
- [43] Ishika Singh, Valts Blukis, Arsalan Mousavian, Ankit Goyal, Danfei Xu, Jonathan Tremblay, Dieter Fox, Jesse Thomason, and Animesh Garg. Progprompt: Generating situated robot task plans using large language models. *2023 IEEE International Conference on Robotics and Automation (ICRA)*, pages 11523–11530, 2022. URL <https://api.semanticscholar.org/CorpusID:252519594>.
- [44] Chan Hee Song, Jiaman Wu, Clay Washington, Brian M. Sadler, Wei-Lun Chao, and Yu Su. Llm-planner: Few-shot grounded planning for embodied agents with large language models. *2023 IEEE/CVF International Conference on Computer Vision (ICCV)*, pages 2986–2997, 2022. URL <https://api.semanticscholar.org/CorpusID:254408960>.
- [45] Sanjana Srivastava, Chengshu Li, Michael Lingelbach, Roberto Martín-Martín, Fei Xia, Kent Vainio, Zheng Lian, Cem Gokmen, Shyamal Buch, C. Karen Liu, Silvio Savarese, Hyowon Gweon, Jiajun Wu, and Li Fei-Fei. Behavior: Benchmark for everyday household activities in virtual, interactive, and ecological environments, 2021. URL <https://arxiv.org/abs/2108.03332>.
- [46] Stone Tao, Fanbo Xiang, Arth Shukla, Yuzhe Qin, Xander Hinrichsen, Xiaodi Yuan, Chen Bao, Xinsong Lin, Yulin Liu, Tse kai Chan, Yuan Gao, Xuanlin Li, Tongzhou Mu, Nan Xiao, Arnav Gurha, Zhiao Huang, Roberto Calandra, Rui Chen, Shan Luo, and Hao Su. Maniskill3: Gpu parallelized robotics simulation and rendering for generalizable embodied ai, 2024. URL <https://arxiv.org/abs/2410.00425>.
- [47] Upwork. Upwork: The world’s work marketplace, n.d. URL <https://www.upwork.com>. Accessed: 2025-01-30.
- [48] Yufei Wang, Zhanyi Sun, Jesse Zhang, Zhou Xian, Erdem Biyik, David Held, and Zackory Erickson. Rl-vlm-f: Reinforcement learning from vision language foundation model feedback, 2024. URL <https://arxiv.org/abs/2402.03681>.
- [49] Zihao Wang, Shaofei Cai, Guanzhou Chen, Anji Liu, Xiaojian Ma, and Yitao Liang. Describe, explain, plan and select: Interactive planning with large language models enables open-world multi-task agents. *arXiv preprint arXiv:2302.01560*, 2023.
- [50] Bowen Wen, Wei Yang, Jan Kautz, and Stan Birchfield. Foundationpose: Unified 6d pose estimation and tracking of novel objects, 2024. URL <https://arxiv.org/abs/2312.08344>.
- [51] Jimmy Wu, Rika Antonova, Adam Kan, Marion Lepert, Andy Zeng, Shuran Song, Jeannette Bohg, Szymon Rusinkiewicz, and Thomas Funkhouser. Tidybot: Personalized robot assistance with large language models. *Autonomous Robots*, 47(8):1087–1102, 2023.
- [52] Zhenyu Wu, Ziwei Wang, Xiuwei Xu, Jiwen Lu, and Haibin Yan. Embodied task planning with large language models. *ArXiv*, abs/2307.01848, 2023. URL <https://api.semanticscholar.org/CorpusID:259342896>.
- [53] Tianbao Xie, Siheng Zhao, Chen Henry Wu, Yitao Liu, Qian Luo, Victor Zhong, Yanchao Yang, and Tao Yu. Text2reward: Reward shaping with language models for reinforcement learning, 2024. URL <https://arxiv.org/abs/2309.11489>.
- [54] Tianbao Xie, Siheng Zhao, Chen Henry Wu, Yitao Liu, Qian Luo, Victor Zhong, Yanchao Yang, and Tao Yu. Text2reward: Reward shaping with language models for reinforcement learning. In *The Twelfth International Conference on Learning Representations*, 2024. URL <https://openreview.net/forum?id=tUM39YTRxH>.
- [55] Wenhao Yu, Nimrod Gileadi, Chuyuan Fu, Sean Kirmani, Kuang-Huei Lee, Montse Gonzalez Arenas, Hao-Tien Lewis Chiang, Tom Erez, Leonard Hasenclever, Jan Humplík, Brian Ichter, Ted Xiao, Peng Xu, Andy Zeng, Tingnan Zhang, Nicolas Heess, Dorsa Sadigh, Jie Tan, Yuval Tassa, and Fei Xia. Language to rewards for robotic skill synthesis. *Conference of Robot Learning 2023*, 2023.
- [56] Lihan Zha, Yuchen Cui, Li-Heng Lin, Minae Kwon, Montse Gonzalez Arenas, Andy Zeng, Fei Xia, and Dorsa Sadigh. Distilling and retrieving generalizable knowledge for robot manipulation via language corrections. *ArXiv*, abs/2311.10678, 2023. URL <https://api.semanticscholar.org/CorpusID:265281528>.
- [57] Mandi Zhao, Shreeya Jain, and Shuran Song. Roco: Dialectic multi-robot collaboration with large language models. *ArXiv*, abs/2307.04738, 2023. URL <https://api.semanticscholar.org/CorpusID:259501567>.

APPENDIX

ADDITIONAL RELATED WORKS

a) Foundation models in reinforcement learning.: The emergence of foundation models has sparked new directions in reinforcement learning, particularly in the context of robotic tasks. Vision-language models (VLMs) have proven effective as both success detectors and zero-shot reward generators [11, 37, 48]. Parallel developments in value learning have explored personalization of multi-objective rewards and in-context value function adaptation [19, 30], highlighting the potential of foundation models to capture nuanced human preferences.

ADDITIONAL METHOD DETAILS

b) Verification questions for domain knowledge.: While reasoning foundation models are strong, long context can result in information loss [7]. Giving the same information in smaller chunks can promote adherence. At the same time, the foundation model is unlikely to completely change strategies once the initial code has been written. We therefore give domain knowledge in the initial coding prompt, then reiterate in a sequence of verification instructions. This results in a new reward variant each time the code is updated. Because different pieces of knowledge are important for different preferences, multiple variants are trained and evaluated. As in prior works [54, 36], we use **iterative error correction** on the first and final variants. Generated reward code is run in the simulator; in case of an error, it is given to `o1-mini` to correct.

ADDITIONAL RESULTS

We see in Fig. 7 and Fig. 8 that ROSETTA performs consistently on various types of language and content, as referenced in the main text. This is maintained in challenging cases like context-dependent language and behavioral feedbacks where reward strategies are nonobvious. It also demonstrates that alignment and optimizability are not the same, but do relate.

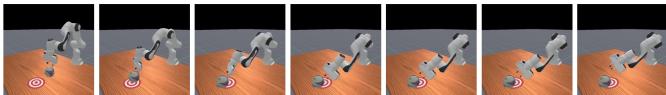
EXAMPLES

In this section, we present examples illustrating how our pipeline processes human feedback, along with its limitations. Additionally, we provide examples demonstrating the necessity of a multi-faceted evaluation framework.

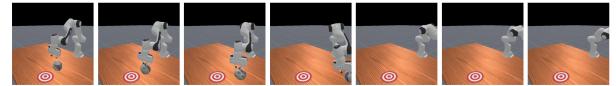
A. Successful Cases in Short-Horizon

Here, we present a sequence of interactions between our pipeline and the annotator, where ROSETTA successfully adapts the policy to the human’s feedback and makes continuous progress.

- **Initial Demonstration:** Robot pushes the ball to the goal.



- **Step 1 Human Feedback:** I like the way the robot uses its claw to push force on the sphere to move it. I want to the robot to push the sphere rightward on the table, but as far as the robot is able to.
- **Step 1 Generated Grounded Feedback:** Push the ball as far to the right on the table as possible.
- **Step 1 Generated Goal:** Push the ball as far to the right on the table as possible.
- **Step 1 Demonstration:** The robot pushes the ball all the way to the right



- **Satisfaction Score:** 87.5
- **Step 2 Human Feedback:** I can see the “effort” of the robot trying to push the ball right. I want to see the robot push the ball in the best spinning motion it can do.
- **Step 2 Generated Grounded Feedback:** Push the ball using a spinning motion.
- **Step 2 Generated Goal:** Push a ball to goal position using a spinning motion.
- **Step 2 Demonstration:** The robot spins the ball sideways, pushes the ball to the right.



- **Satisfaction Score:** 75.0
- **Step 3 Human Feedback:** I like the effort given to perform the task. Although it was not complete, I enjoyed it. It was a hard task. It kind of rolled the ball in a big circle - maybe it could try using its gripper to just rotate the ball?
- **Step 3 Generated Grounded Feedback:** Use the gripper to rotate the ball directly towards the goal instead of moving it in a circular path.
- **Step 3 Generated Goal:** Push a ball to goal position by rotating it directly towards the goal using the gripper.
- **Step 3 Demonstration:** The robot pushes the ball towards the right of the target while rotating it sideways.



- **Satisfaction Score:** 50
- **Step 4 Human Feedback:** I do not want the robot to try to push the ball to the goal position anymore. The robot performed good prior. I want it to try to make the ball rotate in place, maybe by twisting its gripper on top. I want to see the ball spin.
- **Step 4 Generated Grounded Feedback:** Stop trying to push the ball to the goal position. Instead, make the ball

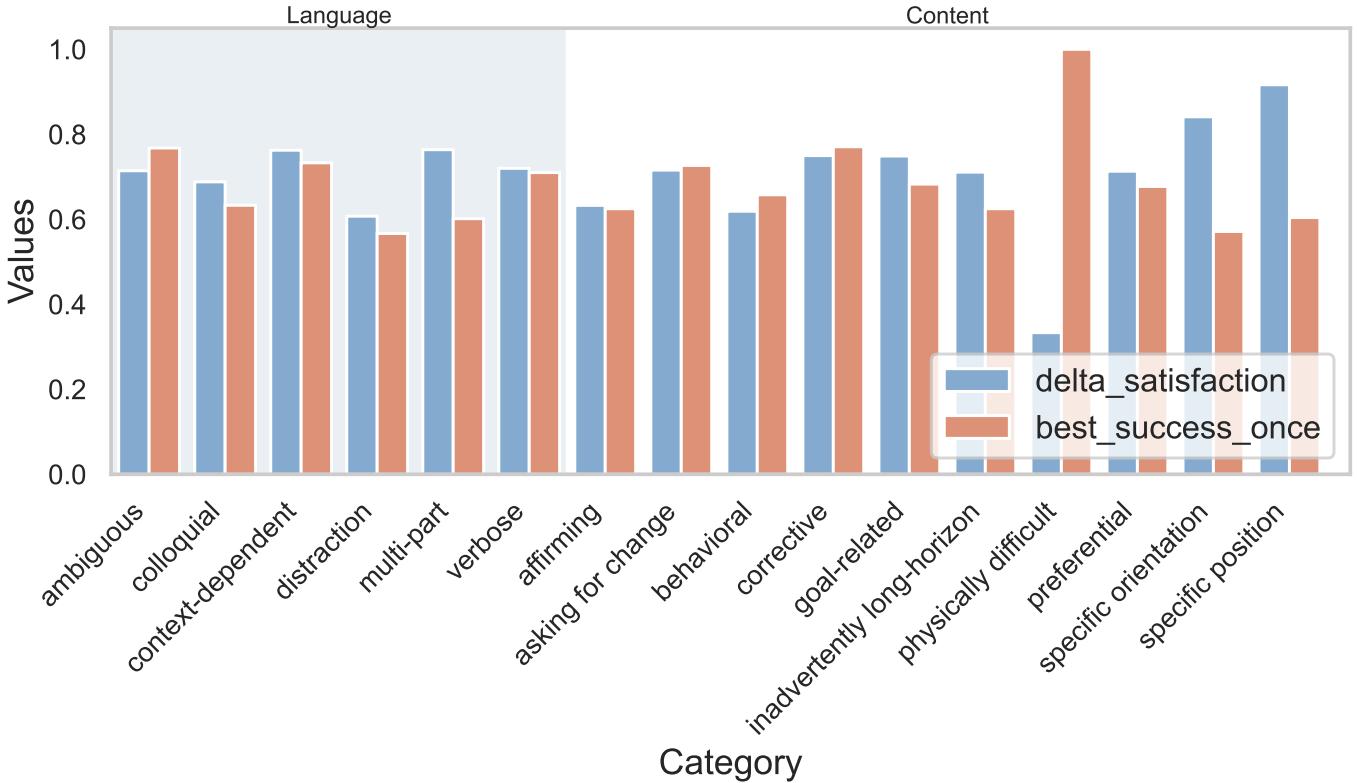


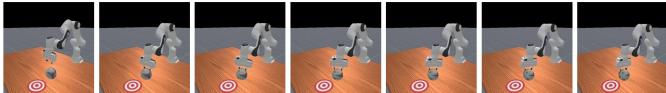
Fig. 7: ROSETTA performance on various categories on **short-horizon** environments. For legibility reasons, we exclude some language categories that foundation models are able to handle without additional domain knowledge, such as 3rd-person POV, 2nd-person POV, no POV, curious tone, directive tone, and suggestive tone. We also exclude conditional and physically impossible feedbacks, which are rare.

# Preferences	Semantic Match				Optimizability		Alignment	
	Grounding	Staging	Coding	Cascading*	Success Rate	Pct Success > 50 (%)	Satisfied (%)	Satisfaction Score
Short Horizon	80	95.7	87.3	84.6	78.1	89.2	90.1	84.8
Long Horizon	36	80.0	90.0	82.9	78.6	82.2	88.8	92.4

TABLE II: Experimental results evaluating semantic alignment, optimization potential, and user satisfaction. Semantic match metrics: expert Likert evaluation on grounding quality, staging quality, coding quality, cascading (product of all three). Optimizability metrics: Success rate: average success rate of best policy for a single preference, Pct Success > 50%: percent runs with success rate above 50%. Alignment: Satisfaction: % preferences where annotator was satisfied, Satisfaction Score: preference annotator Likert evaluation on how much more/less satisfied (50 is neutral). **Note:** Cascading Match excludes cases where expert evaluators found the feedback difficult to interpret.

rotate in place by twisting the gripper on top of it to see the ball spin.

- **Step 4 Generated Goal:** Make the ball rotate in place by twisting the gripper on top of it to see the ball spin.
- **Step 4 Demonstration:** The robot slowly rotates the ball by twisting the gripper.



- **Satisfaction Score:** 100

B. Successful Cases in Long-Horizon

Here, we showcase instances where our pipeline successfully handles feedbacks to long-horizon environments.

- 1) *Example 1: Success Rate: 0.9, Satisfaction Score: 100:*
 - **Human Feedback:** Place the light colored items in one bin and the dark objects in the other.
 - **Feedback Categories:** no pov, context-dependent, preferential, goal-related , specific position, directive, asking for change.
 - **Generated Grounded Feedback:** Place the apple and orange in one bin, and the baseball and tennis ball in the other bin.

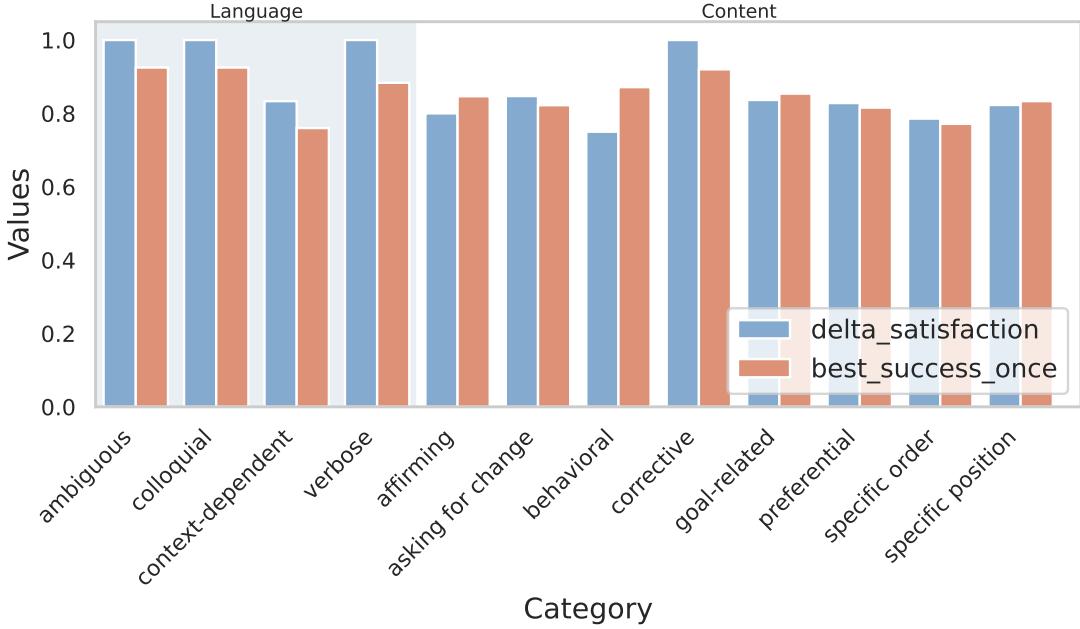


Fig. 8: ROSETTA performance on various categories on **long-horizon** environments. For legibility reasons, we exclude some language categories that foundation models are able to handle without additional domain knowledge, such as 3rd-person POV, 2nd-person POV, no POV, curious tone, directive tone, and suggestive tone. We also exclude conditional, inadvertently long-horizon, physically difficult, distraction, multi-part, and physically impossible feedbacks, which didn't occur in long-horizon experiments.

- **Previous Goal:** Place the apple, orange, baseball, and tennis ball all into the same bin.
- **Generated New Goal:** Place the apple and orange in one bin, and the baseball and tennis ball in the other bin.
- **Previous Demonstration:** The robot picks up the objects and puts them into the white bin one by one.



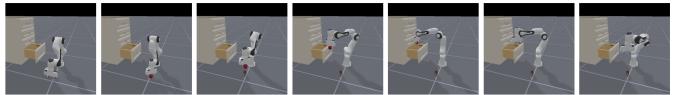
- **New Demonstration:** The robot placed the baseball and tennis ball in the white bin, and apple and orange in the blue bin.



2) *Example 2: Success Rate: 1.0, Satisfaction Score: 100:*

- **Human Feedback:** Can the robot pick up the other items on the floor? It doesn't appear complete with its task leaving the other items there.
- **Feedback Categories:** 3rd-person, verbose, suggestive, preferential, context-dependent, corrective, asking for change.
- **Generated Grounded Feedback:** Pick up the red soup can and place it in the drawer.

- **Previous Goal:** Put apple in drawer.
- **Generated New Goal:** Put Apple and Red Soup Can In Drawer
- **Previous Demonstration** The robot picks up the apple and places it in the drawer.



- **New Demonstration** The robot placed the apple in the drawer, then the soup in the drawer.

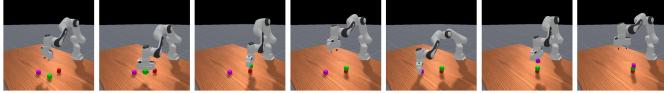


3) *Example 3: Success Rate: 0.6, Satisfaction: 100:*

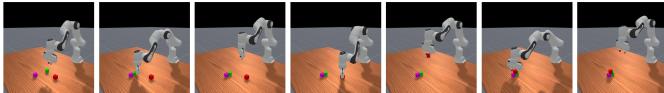
- **Human Feedback:** I am glad the robot was able to completely stack the three cubes in the correct order. I would like the robot to now push the green cube next to the pink cube. After, I want the robot to pick up the red cube and drop it on top of the two cubes.
- **Feedback Categories:** 3rd-person, preferential, behavioral, specific order, specific position, goal-related, asking for change.
- **Generated Grounded Feedback:** Move the green cube next to the purple cube. Then, pick up the red cube and

place it on top of the green and purple cubes.

- **Previous Goal:** Stack the green cube on top of the red cube, then stack the purple cube on top of the green cube.
- **Generated New Goal:** Move the green cube next to the purple cube. Then, pick up the red cube and place it on top of the green and purple cubes.
- **Previous Demonstration:** The robot stacks three cubes together.



- **New Demonstration:** The robot pushes the green cube next to the purple cube and places the red cube on top of them.



C. Examples of Limitations

1) *Limitation 1: Mistake Accumulation:* A specific failure case we observed occurs when the language model propagates errors from the current reward function to the new one. In this case, the LLM mistakenly added a +0.1 offset to the z-coordinate of the target position. In the previous step, due to a correctly defined success condition and some luck, the robot was able to successfully learn the task. However, this error was inherited in the generated reward function, leading to unsuccessful learning in the subsequent step.

- **Previous Reward Function Snippet:**

```
def stage_0_reward():
    # Target position computation
    # Action: pick up the red apple
    # Target position is slightly above
    apple_pos = prev_info['apple_pos']
    target_pos_1 = apple_pos.copy()
    target_pos_1[2] += 0.1
```

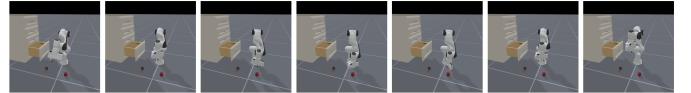
- **Generated Next Step Reward Function Snippet:**

```
def stage_0_reward():
    # Target position computation
    # Action: pick up the red apple
    # Target position is slightly above
    apple_pos = prev_info['apple_pos']
    target_pos_1 = np.array([
        apple_pos[0],
        apple_pos[1],
        apple_pos[2] + 0.1
    ])
```

- **Previous Demonstration:** The robot puts the two objects in the drawer and closes it.



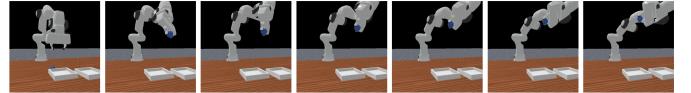
- **New Demonstration:** The robot repeatedly tries to pick up the apple but doesn't lower the gripper enough.



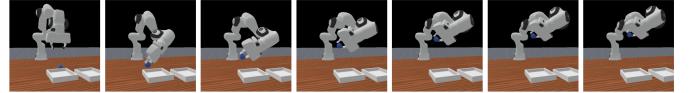
The flawed reward function ended with a 0 success rate and a 0 satisfaction score.

2) *Limitation 2: Content Constraint:* Inadvertent long-horizon scenario.

- **Step 1 Feedback:** I want the robot to release the sphere after placing it.
- **Step 1 Demonstration:** The robot lifts the cube above the bin but fails to release it.



- **Step 2 Feedback:** I want the robot to put the ball in the corner of the bin
- **Step 2 Demonstration:** Still, the robot lifts the cube above the bin but fails to release it.



- **Step 3 Feedback:** I want it to not try to first bring the ball above the corner then release. It seems that's not going to work. It should put it straight down into the bin *the corner to approach from above*
- **Step 3 Demonstration:** The robot picks up the ball and moves it to the corner of the bin. Though this is listed as an example of a fundamental limitation, this final adaptation despite contaminated history shows the power of the modular framework to recover and adapt to helpful human input.



D. Constraints

While ROSETTA accepts unconstrained language, we established certain content constraints for annotators, though we accepted some violations to show the system's limitations. Constraints:

- No temporal dependency. Since the state history is not given to the reward function except one step back in

the action primitive case, we disallowed preferences referencing history. An example: “pause your gripper 2cm above the sphere, then continue down.” This cannot be implemented with history-agnostic masking. The most successful agents paused 2cm above the sphere and never progressed.

- No long-horizon tasks in the continuous control setting - described above. This was violated many times as it can be nonobivous to an annotator.
- To some degree, please accept jitter. Stabilization is possible, but it’s not the default behavior. If you want stabilization, please say so explicitly.
- Avoid asking for multiple goals at once (multi-objective reward). This was rare regardless, as annotators quickly recognized that asking for two things at once was unrealistic.
- Avoid asking for ungrasp in continuous control: this turns out to be difficult to learn since grasping is usually the right move. The algorithm did learn it in many cases, but this was more due to its own sampling leading to a success boost than the dense ungrasping reward.
- Action primitive setting only: can only give feedback on positions, cannot ask for pulling action.

PROMPTS

E. Short Horizon Reward Generation Prompts

To generate the reward function for a short-horizon environment, we follow the steps outlined below. The entire pipeline takes the following inputs:

- **Current Environment Code:** The full ManiSkill environment code, including the current reward function.
- **Grounded Feedback:** Grounded human feedback.
- **Demo Summary:** A generated language description of the demonstration.
- **New Task Goal:** The updated task goal based on the feedback.

The generation process is carried out through a multi-round conversation with GPT-4o, following these steps:

- 1) **Staging:** In this step, the LLM is tasked with planning the reward function based on the feedback. (Prompt 1)
- 2) **Coding:** The LLM is tasked with generating reward function code snippets according to its plan. (Prompt 2)
- 3) **Error Correction 1:** We execute the generated code and ask LLM to regenerate the reward function with the error trace if the code fails.
- 4) **Geometry Review:** The LLM reviews the generated code and corrects any geometry-related mistakes. (Prompt 3)
- 5) **Target Position Reward Review:** The LLM reviews and corrects target position setting mistakes in the generated code. (Prompt 4)
- 6) **Reward Design Review:** The LLM reviews and corrects reward function design mistakes in the generated code. (Prompt 5 and (Prompt 6))
- 7) **Error Correction 2:** We execute the generated code and ask LLM to regenerate the reward function with the error trace if the code fails.

Prompt used:

Short Horizon Staging Prompt

Instructions

You are a reward engineer that is an expert at designing reward functions to solve reinforcement learning tasks. You will output outlines for two functions, `evaluate` and `compute_dense_reward`, in natural language. They should be concrete and ready for implementation.

You will be given:

1. Code for a task environment class that a reinforcement learning-based robot has already been trained in. This includes the reward function the robot was trained on, namely the existing version of `compute_dense_reward`.
2. Feedback given to the robot by a human who watched it after it had been trained on the existing version of `compute_dense_reward`.

You should:

1. Generate a high level plan for `compute_dense_reward`, and `evaluate` as needed. `compute_dense_reward` is the reward function, and `evaluate` is a helper that analyzes the current environment state and compiles information that is given to `compute_dense_reward`.
2. Design a staged reward:

- Split the task into stages and give the agent reward gradually, encouraging it to complete each stage. The reward should therefore accumulate, NOT be all-or-nothing at the end.

- Consider interdependencies and tradeoffs between different task stages and different aspects of the feedback and overall goal. Ensure your reward design isn't counterproductive.

3. If there are aspects of the feedback that it's impossible to incorporate without modifying other methods, say "I cannot do <aspect>" and ONLY incorporate the other parts of the feedback, if there are any.

4. If there are aspects of the feedback that are physically impossible, say "I cannot do <aspect>" and ONLY incorporate the other parts of the feedback, if there are any.

5. Explain your reasoning at each step.

Each stage must be a **single outcome**.

It must be a change in an environment state, not a particular action. It must obey one of the following templates:

- Reward the robot for traveling to < desired position>. Example: "reward the

```

robot for traveling to the point just
left of `cubeA`."
- Reward the robot for getting <desired
object> to <desired position>. Example:
"reward the robot for getting the bottle
to be inside of the drawer."
- Reward the robot for <other single
outcome>. Example: "reward the robot for
moving more smoothly."
- Reward the robot for <other single
descriptor> <other object>. Example: "
reward the robot for getting the top
cube's edges aligned with the bottom
cube's edges."
Tips:
- Notice how the stage templates are
highly atomic - one single outcome.
- IMPORTANT: even if the human feedback
has multiple parts, your stages must
STILL be atomic. Just because the person
lists multiple parts, this doesn't mean
each part is a single stage. One part
may still require multiple atomic stages,
and one atomic stage may contribute to
multiple feedback parts. BE SMART, DON'T
JUST LIST OUT THE FEEDBACK AS YOUR
STAGES.
- Note how the stage templates deal with
changes to the environment (including
the robot) rather than the robot's
actions.

```

```

### Details for `evaluate`
```python
def evaluate(self: BaseEnv) -> Dict[str,
 torch.Tensor]
"""
Return dict is the dict mapping
strings of reward-relevant questions to
their boolean-valued answers for the
batch. So, the values of this dict are
torch. Tensors with bool dtype, where
the first dimension is a batch of
episodes and the second is the boolean
answer to the string question for that
individual episode.

```

Should create a useful set of information. `evaluate` will be called on both the previous state (before the agent took an action) and the current state (after the agent took an action) to calculate reward.

```

"""
```

```

```

### Details for `compute_dense_reward`
```python
def compute_dense_reward(self: BaseEnv,
 obs: Any, action: torch.Tensor, info:
 Dict[str, torch.Tensor]) -> torch.Tensor
"""
Encodes reward for each possible
action based on `evaluate` output
dictionary and other current environment

```

info (environment instance attributes).

Incorporates human feedback as given.

Obeys the following structure:

1. Stage reward

- Task is split into stages and reward is given to the agent gradually, encouraging it to complete each stage. The reward accumulates.

- Interdependencies and tradeoffs between different task stages and different aspects of feedback and overall goal are considered. Reward design is not overall counterproductive to meet short-term goals.

2. Extra success bump for successful episodes

3. Return reward value

"""

Original code:

```

```python
{ENVIRONMENT CODE}
```

```

Current task description: {NEW TASK GOAL}

Robot execution description: {DEMO SUMMARY}

Human's feedback: {GOUNDED FEEDBACK}

## Instructions

Think step-by-step to make a high-level plan for rewriting `evaluate` and `compute\_dense\_reward`. The plan should be a series of stages.

- Don't code yet, just plan the stages.
- Consider dependencies and conflicts between task stages, and create a plan that doesn't do anything counterproductive.
- Carefully consider the physical aspects of the task.

- Plan realistic paths

- Consider the physical state the robot is in after each stage. Write the next stage to build directly on it.

## RULES YOU MUST FOLLOW:

1. Incorporate human feedback as given.
2. Do not add anything that contradicts the feedback.

3. Do not invent your own changes or speculate about what the feedback is going for.

4. Do not add anything counterproductive to the overall goal.

5. Make every stage atomic.

6. Make the plan complete - think about all the atomic stages the robot needs to achieve every part of the feedback, not

just the final ones.

7. NEVER ask the robot to release an object from the gripper.
8. NEVER ask the robot to first move above the desired location, below desired location, then release or lower down or move up. Just have it go straight to the desired location.

### Short Horizon Coding Prompt

#### # Instructions:

1. Code the reward function based on the stages.
  - a. Use the Code Block below wherever possible.
  - b. Follow the Checklist below.
2. Only output methods you are editing.
3. If you are editing a method, output the whole edit method, not just your edits.
4. Don't introduce new methods, not even helper methods. Just edit `compute\_dense\_reward` and `evaluate`.
5. Comment your code as needed.
6. If there are aspects of the feedback that it's impossible to incorporate without modifying `\_load\_scene` or `\_initialize\_episode`, say "I cannot do < aspect>" and ONLY incorporate the other parts of the feedback, if there are any.
7. Explain your implementation.
8. Explain checklist adherence. Be concise.

1. Code the reward function on the stages. Write a short chain of reasoning before your code, to explain your reasoning.
  - a. Use the Code Block below wherever possible.
  - b. Follow the checklist below.
  - c. Comment your code as needed.
2. Only output methods you are editing.
3. If you are editing a method, output the whole edit method, not just your edits.
4. Don't introduce new methods, not even helper methods. Just edit `compute\_dense\_reward` and `evaluate`.
5. If there are aspects of the feedback that it's impossible to incorporate without modifying `\_load\_scene` or `\_initialize\_episode`, say "I cannot do < aspect>" and ONLY incorporate the other parts of the feedback, if there are any.

```
Code Blocks for `compute_dense_reward`

Make Robot Reach Target Positions
In `compute_dense_reward`:
- **Minimize the distance** between the
```

object's current position and the target position in the reward function.

- \*\*Normalize and smooth distances\*\* using functions like `torch.tanh`:

```
'''python
```

```
transport_reward = 1.0 - torch.tanh(
 torch.linalg.norm(target_pos - obj.pos())
) # max 1.0, decreases with distance
'''
```

- \*\*Don't just give a boost when the target position has already been reached\*\* The robot will get no guidance during movement and be unable to begin.

#### # Function signatures

##### ## Details for `evaluate`:

```
'''python
```

```
def evaluate(self: BaseEnv) -> Dict[str,
 torch.Tensor]
 """
```

Return dict is the dict mapping strings of reward-relevant questions to their boolean-valued answers for the batch. So, the values of this dict are torch.Tensors with bool dtype, where the first dimension is a batch of episodes and the second is the boolean answer to the string question for that individual episode.

Should create a useful set of information. `evaluate` will be called on both the previous state (before the agent took an action) and the current state (after the agent took an action) to calculate reward.

Always contains a key called "success" that maps to the success condition

```
"""
'''
```

```
'''
```

##### ## Details for `compute\_dense\_reward`:

```
'''python
```

```
def compute_dense_reward(self: BaseEnv,
 obs: Any, action: torch.Tensor, info:
 Dict[str, torch.Tensor]) -> torch.Tensor
 """
```

Encodes reward for each possible action based on `evaluate` output dictionary and other current environment info (environment instance attributes).

Incorporates human feedback as given.

Obeys the following structure:

1. Stage reward

- Task is split into stages and reward is given to the agent gradually, encouraging it to complete each stage. The reward accumulates. Each stage's reward is dense wherever possible.

```

 - Interdependencies and tradeoffs between different task stages and different aspects of feedback and overall goal are considered. Reward design is not overall counterproductive to meet short-term goals.
 2. Extra success bump for successful episodes
 3. Return reward value
 """
...
Reward Function Checklist

Coding Best Practices

- **Use `clone()`** when calculating and mutating `torch.Tensor`'s to avoid unintended reward changes

Selecting Target Positions

- When defining target positions, **specify all coordinates (x, y, z)**. Do not leave any unrestricted.
- `<element>.pos()` returns the **center position** of the element. Adjust with offsets if targeting the top, bottom, or sides.
- **Understand geometry and dimensions** by reading the environment code.
 - **Example:** If placing an object inside a box, account for wall thickness.

 - **Example:** If aligning an object with the edge of a target, consider the target's shape.

Staged Reward Masking

- **Use torch masking** to activate rewards for a stage **only after** its prerequisites are met.
- **Example:** Two stages (1) grasp `bottleA`, (2) move `bottleA` to `boxA`
    ```python
    # Assume 'is_bottleA_on_boxA' and 'is_bottleA_grasped' are in info and the target position for `bottleA` is defined
    # Stage 2 reward - moving `bottleA` to `boxA`
    move_reward = torch.tanh(torch.linalg.norm(target_pos - bottleA.pos()))
    ```

 # Reward moving `bottleA` to its target position `target_pos` only after it's grasped
 reward[info['is_bottleA_grasped']] += move_reward[info['is_bottleA_grasped']]
    ```

- **Mask based on completed stages**, not the current one. Example of bad masking:
    ```python
 # Incorrect: Masking on the current
```

```

```

stage's completion
reward[info['is_bottleA_on_boxA']] += move_reward[info['is_bottleA_on_boxA']]
    # This fails because it doesn't reward reducing the distance between `bottleA` to `boxA` until the distance is zero. The robot therefore doesn't get dense process reward.
```
- **Don't reward conflicting stages simultaneously**.
- **Maintain non-decreasing rewards** to encourage progression.
 - **Example:** If the robot must grasp `objectA`, place it, ungrasp, then grasp `objectB`:
 - Continue rewarding the grasp of `objectA` even when it's being placed.
 - Mask the reward for grasping `objectB` based on `objectA` being at the target location, not whether `objectA` is grasped.

```

#### ### Reward Component Weighting

```

- **Equalize the maximum values and shapes of each stage's reward components**.
- **Prevent reward imbalance for different stages** or the robot may fail to progress on the task because the additional reward is relatively small.

```

#### ### Success Boost

```

- **Add a reward boost** when the task is successfully completed to emphasize successful episodes.
 - Ensure `info['success']` is a boolean indicating success.
 - Example code:
            ```python
            success_boost_val = 5.0 # Adjust to be 1/4 of total possible reward so far
            reward[info['success']] += success_boost_val
            ```


```

{MANISKILL ENVIRONMENT DOCUMENTATION}

#### Short Horizon Geometry Review Prompt

```

- Verify that for each object, this code handles the fact that `<element>.pos()` returns the center location. Common pitfalls:
 - Not applying the right offsets when placing two objects relative to each other. E.g. half-width, radius, etc.
 - Verify that this code considers the physical attributes of each object and how they might offset target positions. Common pitfalls:
 - Thickness of box walls

```

- Verify that this code uses x as the front-back axis and y as the left-right axis. z is still the up-down axis.
- Verify that when applying penalties, this code does not OVER-penalize. For example, if slowness is required, set a low upper bound for speed, but do not penalize it entirely or the robot will be stalled.

1. Write out your verification step-by-step.
2. Edit the code as needed according to your explanation. Comment your changes.
3. Only output methods you are editing.
4. If you are editing a method, output the whole method, not just your edits.
5. Don't introduce new methods, not even helper methods. Just edit `compute\_dense\_reward` and `evaluate`.

#### Short Horizon Target Position Review Prompt

- Verify that each of the three coordinates is considered for every position and offset in the code. Common pitfalls:
  - Forgetting the z-component
  - Ignoring one or two coordinates when setting a target position. If the robot is not given constraints in some axis, it could do anything, leading to a crash into something else.
- Verify that specific target positions are always set. Common pitfalls:
  - Simply incentivizing the robot to go in a certain direction (e.g. "down" or "below an object"). It should always be pushed toward a SPECIFIC POINT IN SPACE, or it won't stop and will fly wildly.

1. Write out your verification step-by-step.
2. Edit the code as needed according to your explanation. Comment your changes.
3. Only output methods you are editing.
4. If you are editing a method, output the whole method, not just your edits.
5. Don't introduce new methods, not even helper methods. Just edit `compute\_dense\_reward` and `evaluate`.

#### Short Horizon Reward Design Review Prompt

- Verify that the reward is \*dense\* when, and ONLY when, you want the robot to gradually approach a certain state. "Dense" means a continuous function that gives more and more reward as the robot approaches the right position, rather than a step function only reward it once

it's reached.

- Distance, angular difference, velocity - all continuous values that can have dense, continuous rewards
  - Traveling to a location gradually and opening/closing a gripper to a certain point gradually - ALWAYS DENSE.
- Verify that all \*penalties\* are NOT dense. Examples:
  - To slow the robot down, there should be a penalty on speed that is NOT dense. You want it to just stay below a specific speed, not get more reward the slower it is.
  - TO HAVE THE ROBOT GO SLOW, THE CODE SHOULD SIMPLY SET A CONSTANT UPPER BOUND ON SPEED. DENSE REWARD DOES NOT HELP HERE.
  - To have the robot to keep its gripper closed, the penalty on gripper opening should not be dense - you want it to stay below a certain opening, not get more reward the more closed it is.
- Verify that the code actually requires the robot to reach its target position. Common pitfalls:
  - Defining a "near" threshold that is larger than the "at" threshold for a target position, then not requiring the agent to move once it's "near" even if it's not "at".

1. Write out your verification step-by-step.
2. Edit the code as needed according to your explanation. Comment your changes.
3. Only output methods you are editing.
4. If you are editing a method, output the whole method, not just your edits.
5. Don't introduce new methods, not even helper methods. Just edit `compute\_dense\_reward` and `evaluate`.

#### Short Horizon Masking Review Prompt

- Verify that the reward \*\*never decreases\*\* during the progression of the task, so that the robot isn't disincentivized from making progress.
  - The code should only mask on genuine prerequisites
  - The reward should be enabled even when the stage is complete
    - For example, if the robot needs to grasp an object to carry it to a location and then let it go, give the grasp reward not only when the gripper is ready to grasp, but also after the object has been carried to the location and ungrasped.
  - Verify that no stage reward components are masked prematurely.
    - Example: reward component guides the

robot to put `objA` next to `objB`. Masking this with `info["is\_objA\_next\_to\_objB"]` means it'll only get reward after it succeeds, so it will never get started.

- Example: reward component guides the robot to travel to point `target\_pos`. Masking this with `info["is\_near\_target\_pos"]` means it'll only get reward after it succeeds, so it will never get started.

1. Write out your verification step-by-step.
2. Edit the code as needed according to your explanation. Comment your changes.
3. Only output methods you are editing.
4. If you are editing a method, output the whole method, not just your edits.
5. Don't introduce new methods, not even helper methods. Just edit `compute\_dense\_reward` and `evaluate`.

## F. Long Horizon Reward Generation Prompts

To generate the reward function for a long-horizon environment, we follow the steps outlined below. The entire pipeline takes the following inputs:

- **Current Environment Code:** The full ManiSkill environment code, including the current reward function.
- **Grounded Preference:** Grounded human preference.
- **Demo Summary:** A generated language description of the demonstration.
- **Current Task Goal:** The task goal that the policy is currently attempting to achieve.
- **New Task Goal:** The updated task goal based on the preference.
- **Environment Information Key:** Dictionary Keys of the observation space, with corresponding descriptions.
- **Environment Setup Description:** A description of the environment setup.
- **Error Correction:** We execute the generated code and ask LLM to regenerate the reward function with the error trace if the code fails.

The generation process is carried out through a multi-round conversation with GPT-4o, following these steps:

- 1) **Staging:** In this step, the LLM is tasked with planning the reward function based on the preference. (Prompt 7)
- 2) **Coding:** The LLM is tasked with generating reward function code snippets according to its plan. (Prompt 8)
- 3) **Geometry Review:** The LLM reviews the generated code and corrects any geometry-related mistakes. (Prompt 9)
- 4) **Reward Normalization Review:** The LLM reviews and corrects normalization-related mistakes in the generated code. (Prompt 10)
- 5) **Code Cleanup:** The LLM reviews and resolves any coding or formatting errors in the generated code. (Prompt 11)

- 6) **Construct Reward Function:** The final reward function is constructed by inserting the generated code snippets into Template 12.

### Prompt used:

#### Long Horizon Staging Prompt

##### # Instructions

You are a reward engineer that is an expert at designing reward functions to solve reinforcement learning tasks. We have trained a reinforcement learning-based robot in a task environment. We then demonstrate the policy to a human who gave feedback on the robot's performance. Now, we want to design a reward function that incorporates the human's feedback. You will output an outline for the reward function `compute\_dense\_reward`, in natural language. It should be concrete and ready for implementation.

You will be given:

1. `Original Code`: Code for a task environment class, including the reward function robot has already been trained in, namely `compute\_dense\_reward`.
2. `Original Task Goal`: The original task goal of the robot before the feedback was given.
3. `Simulation Environment Setup`: Description of the simulation environment.
4. `Demonstration Summary`: Summary of the robot's performance during the demonstration.
5. `Human Feedback`: Feedback given to the robot by a human who watched it after it had been trained on the existing version of `compute\_dense\_reward`.
6. `New Task Goal`: The new task goal for the robot after the feedback has been incorporated.

You should:

1. Generate a high level plan for `compute\_dense\_reward`.
2. Design a staged reward:
  - Split the task into stages and give the agent reward gradually, encouraging it to complete each stage. The reward should therefore accumulate, NOT be all-or-nothing at the end.
    - Consider interdependencies and tradeoffs between different task stages and different aspects of the feedback and overall goal. Ensure your reward design isn't counterproductive.
  - 3. If there are aspects of the feedback that it's impossible to incorporate without modifying other methods, say "I cannot do <aspect>" and ONLY incorporate

the other parts of the feedback, if there are any.

4. If there are aspects of the feedback that are physically impossible, say "I cannot do <aspect>" and ONLY incorporate the other parts of the feedback, if there are any.

5. Explain your reasoning at each step.

```
Design details
`compute_dense_reward`
```

There are three stage templates you can use. You CANNOT use anything else. The robot is ONLY capable of these three stages.

```
"pick up"
```

Template:

- Action: reward the robot for picking up <desired object>.
- Outcome: <desired object> is in the robot's gripper.

Example:

- Action: reward the robot for picking up `red\_cube`.
- Outcome: `red\_cube` is in the robot's gripper.

```
"place"
```

Template:

- Action: reward the robot for placing <desired object> <desired position>.
- Outcome: <desired object> is <desired position>.

Example:

- Action: reward the robot for placing `red\_cube` next to `sphereB`.
- Outcome: `red\_cube` is next to `sphereB`.

```
"push"
```

Template:

- Action: reward the robot for pushing <desired object> to <desired position>.
- Outcome: <desired object> is <desired position>.

Example:

- Action: reward the robot for pushing `red\_cube` just left of the center of the target.
- Outcome: `red\_cube` is just left of the center of the target.

# Output format

Your output should be:

An ordered list of stage plans. Format:

```
```markdown
```

```
## Stage <stage number>: <language description of stage number>
- Stage template: "<pick up or place>"
  - **Action:** <language description of action>
  - **Outcome:** <language description of outcome>
```

- **Dependencies:** <reasoning about any dependencies with previous stages>
- **Other reasoning:** <whatever you think is important to note!>

Examples:

```
```markdown
```

```
Stage 1: Pick up `obj1`
- Stage template: "pick up"
 - **Action:** Reward the robot for picking up `obj1`.
 - **Outcome:** `obj1` is in the robot's gripper.
 - **Dependencies:** The robot can do this easily, so there aren't prior dependencies.
 - **Other reasoning:** [open-ended, you will not be provided with an example]
```
```

```
```markdown
```

```
Stage 4: Put `obj2` next to `obj1`.
- Stage template: "place"
 - **Action:** Reward the robot for placing `obj2` next to `obj1`.
 - **Outcome:** `obj2` is next to `obj1`.

 - **Dependencies:** Requires that the robot is grasping `obj2`.
 - **Other reasoning:** [open-ended, you will not be provided with an example]
```
```

Notice that stage index starts from 0.

```
## Original Code:
```

```
```python
{ENVIRONMENT CODE}
```
```

```
## Original Task Goal: {CURRENT TASK GOAL}
```

```
## Simulation Environment Setup: {ENVIRONMENT SETUP DESCRIPTION}
```

```
## Demonstration Summary: {DEMO SUMMARY}
```

```
## Human Feedback: {GROUNDED FEEDBACK}
```

```
## New Task Goal: {NEW TASK GOAL}
```

Think step-by-step to make a high-level plan for writing `compute_dense_reward`. The plan should be a series of stages.

- Don't code yet, just plan the stages.
- Consider dependencies and conflicts between task stages, and create a plan that doesn't do anything counterproductive.

RULES YOU MUST FOLLOW:

1. Use ONLY the stage templates you've been given.

2. Incorporate human feedback as given.
3. Do not add anything that contradicts the feedback.
4. Do not invent your own changes or speculate about what the feedback is going for.
5. Try accomplish the task goal with minimal stages. Long plans are harder to train on.
6. Make the plan complete - think about all the atomic stages the robot needs to achieve every part of the feedback, not just the final ones.

Long Horizon Coding Prompt

Excellent. Now write the relevant code for each stage.

Instructions:

1. Don't add your own helper methods. Only edit what I've told you to edit.
 2. Go through the coding tips below.
 3. Explain your implementation.
 4. If there are aspects of the feedback that are physically impossible, say "I cannot do <aspect>" and ONLY incorporate the other parts of the feedback, if there are any.
 5. Number of stages should match the number of stages in the plan. It can be different from the number of stages in the original code.
- # How to calculate target positions and position rewards

Coding best practices

- Pay attention to the 'Original Code' and the 'Simulation Environment Setup' given to you earlier.
- All positions are numpy arrays of shape (3,). Make sure you don't modify the content in info dictionaries.
- = Don't worry about missing arguments

How to set a target position for the robot to pick at/place at.

- Object coordinates are x, y, and z coordinates. **Explicitly reason about every coordinate when setting the target position**.
- Note that those are x, y, z coordinates of the *center* of objects.
 - So when setting target positions or getting object positions, if you want the top, bottom, or sides of an object, add the right offsets.
 - Otherwise, make sure you're reasoning about the center.
 - Consider common sense physical issues.
 - **Read the environment code to understand geometry and dimension values
 - ** Examples:

- A box has walls, so if you want to put something inside the box, consider its wall width.

- A target might be a circle or a square - if you want to put something at the edge of the target, consider its shape.

- Remember that direction matters, not just distance. Let's say your intended target position is two block side-lengths away from a block center. You can't take the block center, then tell the robot to go two block side-lengths away from that. It could go two block side-lengths in any direction! You have to calculate your intended position, unambiguously.

How to write a reward component that gets the robot to choose the right location

- Add a reward component that minimizes the difference between the position the robot is currently planning to go to, and the target position you set
- Normalize and smooth these differences with a function like `np.tanh`.
- For example, if the robot has selected position `current_selected_pos` and you set target position `target_pos`, you can take the hyperbolic tangent of the norm of the difference between these two.

- You can also increase the coefficient on the norm within the `np.tanh` to encourage `target_pos` more aggressively, you can subtract from 1.0 so that the overall reward ranges from 0 to 1 and increases as distance decreases, and/or you can use a different normalizing function based on the reward landscape you want.

- **Design based on what we need from this reward component.**

- DON'T give a step function-like boost that only activates when the object has reached its target position. If you do this, the agent won't be able to get started.

Documentation of function inputs
Functions take in two arguments from the environment: `prev_info` and `cur_info`. These are dictionaries with the following keys:

{ENVIRONMENT INFORMATION KEYS}

`prev_info` represent the environment state BEFORE `action` was taken and `cur_info` represent the state AFTER `action` was taken.

Simulation Environment Setup: {
ENVIRONMENT SETUP DESCRIPTION}

```

## Demonstration Summary: {DEMO SUMMARY}

## Human Feedback: {GROUNDED HUMAN
FEEDBACK}

## New Task Goal: {NEW TASK GOAL}

# Your task:

Fill out the TODOs in this markdown to
get reward. Fill out a new copy of the
markdown for every stage. Write a short
chain of reasoning before each code
block to explain your reasoning.

```markdown
stage N target action: # TODO: select [`pick`, `place`, `push`]. Select EXACTLY
the one given to you in the plan - DO
NOT make your own judgement call.
```
```python
def compute_target_position_stageN(self,
prev_info, cur_info):
"""
Defines the target position for the
robot's action - the location it needs
to pick at/place at/push to.
Has no return. The function ends in
the definition of `target_pos_1` and
`target_pos_2`.
Arguments:
- `self (BaseEnv)`: gives access
to environment attributes and method
calls.
- `prev_info (dict[str, Any])`:
state representation of the environment
state BEFORE `action` was taken.
- `cur_info (dict[str, Any])`:
same as `prev_info`, except from the
state AFTER `action` was taken.
"""
TODO: implement target position
for stageN's target action based on
environment.
If the action is `pick` or `place`,
target_pos_1 must be a 3D position
indicating the target position for the
action, and target_pos_2 must be None.
If the action is `push`,
target_pos_1 must be a 3D position
indicating the target starting position
for the push action, and target_pos_2
must be a 3D position indicating the
target ending position for the push
action.
target_pos_1 = ...
target_pos_2 = ...
```
```python
def compute_target_pos_reward_stageN(
self, prev_info, cur_info,

```

```

current_selected_pos_1,
current_selected_pos_2, target_pos_1,
target_pos_2):
"""
Sets a reward to encourage the robot
to take the action at `target_pos_1` and
`target_pos_2`. This reward should be
dense, setting a continuous-valued
penalty for any difference between
`current_selected_pos_1` and
`current_selected_pos_2` (the location
the robot IS CURRENTLY PLANNING to pick
at/place at/push to) and `target_pos_1` and
`target_pos_2` (the location the
robot SHOULD pick at/place at/push to).
Has no return. The function ends in
the definition of `reward`.

Arguments:
- `self (BaseEnv)`: gives access
to environment attributes and method
calls.
- `prev_info (dict[str, Any])`:
state representation of the environment
state BEFORE `action` was taken.
- `cur_info (dict[str, Any])`:
same as `prev_info`, except from the
state AFTER `action` was taken.
- `current_selected_pos_1` and
`current_selected_pos_2` (numpy.ndarray):
the pos the robot IS CURRENTLY PLANNING
TO take the action at
- `target_pos_1 (numpy.ndarray)` and
`target_pos_2 (numpy.ndarray)`:
`target_pos` defined in
`compute_target_position_stageN` - the
pos the robot SHOULD take the action at

Notice that current_selected_pos_2
and target_pos_2 are None if the action
is `pick` or `place`. Do not use them in
this case.

This function will only be called if
selected action equals target action.
In other words, current_selected_pos_2
and target_pos_2 will be both None or
both numpy arrays.
"""
reward = # TODO implement a *dense*
and normalized* reward for guiding the
robot to do `target_action` at
`target_pos`s, i.e. align
`current_selected_pos_1` and
`current_selected_pos_2` with
`target_pos_1` and `target_pos_2`. Use the
`target_pos_1` and `target_pos_2` param,
don't calculate your own.
- Feel free to use normalization
functions like `np.tanh`. Your reward
MUST be normalized to between -1 and 0.
- Ensure your reward is *dense*.
Do not give a sudden boost for reaching
the target position. Instead, make sure
your reward implementation gradually and
continuously guides the robot to target

```

positions. Otherwise, the robot won't be able to get started.  
```

```
```python
def stageN_success(info):
 """
 Return true if the robot has successfully completed stageN, else return false.
```

Arguments:  
- `info` (dict[str, Any]): state representation of the current environment state.

Returns:  
- `bool`: True if the robot has successfully completed stageN, else False.  
"""
# TODO
```
```

Don't write `compute\_dense\_reward` as a whole. Only write the functions I asked for.

### Long Horizon Reward Function Geometry Review Prompt

Review the setup description again:

{ENVIRONMENT SETUP DESCRIPTION}

- For every target position, did you specify all three coordinates?
  - Did you set target positions **exactly** where you desire the robot to go???
- Common pitfalls:
- Adding a small error threshold to the target position. Always allow a bit of error when calculating a **\*boolean check\*** in `stageN\_success`, but the target positions themselves should have no error.Ã¤
  - Did you reason about the dimensions of each object and how they might impact target positions?
  - Picking an object up requires positioning the gripper around the center of the object. Did you consider this? In other words, did you set the target position to the center of the object?

Verify. If you need to make any edits, do so.

1. Only output functions you are editing.
2. If you are editing a function, output the whole thing. Only do so once, with all corrections made.

### Long Horizon Reward Normalization Review Prompt

- Did you consider the range of your normalization functions correctly? Common pitfalls: make sure the range of the reward is -1 to 0.
- Did you consider sensitivity thoughtfully? Common pitfalls: not having tolerance for small errors in the reward and success calculation.

Verify. If you need to make any edits, do so.

1. Only output functions you are editing.
2. If you are editing a function, output the whole thing. Only do so once, with all corrections made.

### Long Horizon Reward Function Cleanup Prompt

- Did you make sure not to include return statements in all `compute\_target\_position\_stageN` and `compute\_target\_pos\_reward\_stageN`, and instead just define `target\_pos` and `reward`, respectively?
- Did you set any new instance variables, i.e. did you create any new `self.< varname>`? You should not - you should just set `target\_pos` and `reward` as regular variables. I will handle the rest.
- Did you use the right datatypes? All positions should be numpy arrays of shape (3,), rewards should be floats, and `stageN\_success` returns boolean.

Verify. If you need to make any edits, do so.

1. Only output functions you are editing.
2. If you are editing a function, output the whole thing. Only do so once, with all corrections made.

### Long Horizon Reward Function Template

```
def evaluate(self):
 info = self._get_obs_info()

 def stage0_success(info):
 <GENERATED STAGE 0 SUCCESS CONDITION>
 ...

 def stageN_success(info):
 <GENERATED STAGE N SUCCESS CONDITION>

 info["stage0_success"] =
stage0_success(info)
```

```

...
info["stageN_success"] =
stageN_success(info)

info["success"] = torch.tensor(False)

if self.cur_stage==N:
 info["success"] = torch.tensor(
info["stageN_success"])

return info

def compute_dense_reward(self, prev_info,
cur_info, action, **kwargs):
 reward_components = dict((k, 0.0)
for k in self.reward_components)
 current_selected_action = np.argmax(
action[:len(self.task_skill_indices.keys
())])

 if current_selected_action in [0, 1]:
 current_selected_pos_1 = action[
len(self.task_skill_indices.keys()):len(
self.task_skill_indices.keys())+3]
 current_selected_pos_2 = None
 else:
 current_selected_pos_1 = action[
len(self.task_skill_indices.keys()):len(
self.task_skill_indices.keys())+3]
 current_selected_pos_2 = action[
len(self.task_skill_indices.keys())+3:
len(self.task_skill_indices.keys())+6]

 def stage_0_reward():
 <GENERATED TARGET POSITION AND
ACTION DEFINITION>

 if current_selected_action ==
target_action:
 <GENERATED DISTANCE
DEFINITION>

 reward_components["afford"] =
(1 + reward) * 5.0

 if cur_info["stage0_success"]:
 reward_components["success"] =
10.0
 return reward_components

 ...

 if self.cur_stage==0:
 reward = stage_0_reward()
 ...
 if self.cur_stage==N:
 reward = stage_N_reward()

 if (self.cur_stage == 0) and
cur_info["stage0_success"]:
 self.cur_stage = 1
 ...
 if (self.cur_stage == N-1) and

```

```

cur_info["stage{N-1}_success"]:
 self.cur_stage = N
 return reward

```

### G. Preference Grounding Prompt

Feedback grounding consists of two stages: (1) translating a demonstration video and its trajectory into a language-based description, and (2) leveraging the language description and human feedback to generate grounded feedback and update task goals.

*1) Demonstration to Language Description:* To address the Vision-Language Action (VLA) model's limitations in spatial and motion understanding, we process each demonstration by decomposing it into frames and augmenting them with state information, including object 3D positions and gripper states.

*a) Short-Horizon Descriptions:* We process short-horizon descriptions in the following steps:

- 1) Sample frames at every 5-frame interval.
- 2) For each sampled frame, extract object positions, states, and the corresponding video frame, then prompt GPT-4o with Prompt 13 to generate a state description.
- 3) For the transitions between sampled frames, input the consecutive state descriptions into GPT-4o with Prompt 15 and request a description of the motion occurring between them.
- 4) Compile all state and motion descriptions into an interleaved sequence of states and actions.

*b) Long-Horizon Descriptions:* For long-horizon descriptions, we segment the demonstration into a sequence of primitive actions and process them as follows:

- 1) Generate a separate language description for each action's start and end state by providing GPT with the corresponding video frame and state information using Prompt 14.
- 2) Provide the start state description, end state description, primitive action type, and action parameters as input to GPT-4o with Prompt 16, requesting a language-based description of the action.
- 3) Compile all state and motion descriptions into an interleaved sequence of states and actions.

#### Prompts used:

##### Short Horizon State Description Prompt

Given the image from a robotic simulation, a description of the setup, and state information, write a caption describing the scene.

## Your response should be similar to the following examples:

EXAMPLE 1: A robot gripper is slightly above the sphere. The sphere is on the table, next to the bin.

EXAMPLE 2: The robot is holding a blue cube above the orange cube. The orange cube is on stacked on top of the pink cube.

```

Input
Setup Description: {ENVIRONMENT SETUP DESCRIPTION}
Here is the state information: {STATE}
Objects do not float. If an object is elevated, it is either held by the robot, stacked on top of another object, or inside a drawer or a bin.

<ENCODED FRAME>

```

### Long Horizon State Description Prompt

Given the image from a robotic simulation, a description of the setup, and state information, write a caption describing the scene.

## Your response should be similar to the following examples:

EXAMPLE 1: A robot gripper hovers above a wooden table, holding a green cube, while a red cube and a purple ball rest on the table surface.

EXAMPLE 2: The robot is holding a green ball above the table. There are two cubes stacked together on the table. The red cube is on top of the purple cube.

## Input

Setup Description: {ENVIRONMENT SETUP DESCRIPTION}

Here is the state information: {STATE}

Objects do not float. If an object is elevated, it is either held by the robot, stacked on top of another object, or inside a drawer or a bin.

<ENCODED FRAME>

### Short Horizon Action Description Prompt

Your job is to generate a language description of a robot's action based on

- (1) START STATE: a dictionary containing the state and position of objects before the action,
- (2) START STATE DESCRIPTION: the language description of the start state,
- (3) END STATE: a dictionary containing the state and position of objects after the action,
- (4) END STATE DESCRIPTION: the language description of the end state, and "

Environment description: {ENVIRONMENT SETUP DESCRIPTION}

EXAMPLE 1: The robot released the blue cube on top of the green cube,

EXAMPLE 2: The robot picks up the blue cube.

Here are the inputs

```

START STATE: {START STATE}
START STATE DESCRIPTION: {START STATE LANGUAGE DESCRIPTION}
END STATE: {END STATE}
END STATE DESCRIPTION: {END STATE LANGUAGE DESCRIPTION}
Now generate a description of the robot's action. Focus on the coordinates.
State description might be wrong.

```

### Long Horizon Action Description Prompt

Your job is to generate a language description of a robot's action based on

- (1) START STATE: a dictionary containing the state and position of objects before the action,
- (2) START STATE DESCRIPTION: the language description of the start state,
- (3) END STATE: a dictionary containing the state and position of objects after the action,
- (4) END STATE DESCRIPTION: the language description of the end state, and
- (5) ACTION DESCRIPTION: the parameter of the action command to the robot.

Environment description: {ENVIRONMENT SETUP DESCRIPTION}

Your response should be one or two sentences long and should be similar to the following examples:

EXAMPLE 1: The robot successfully picks up the green cube.  
 EXAMPLE 2: The robot tries to place down the red cube on the green cube. However, the red cube ended on the table.

Here are the inputs

```

START STATE: {START STATE}
START STATE DESCRIPTION: {START STATE LANGUAGE DESCRIPTION}
END STATE: {END STATE}
END STATE DESCRIPTION: {END STATE LANGUAGE DESCRIPTION}
ACTION DESCRIPTION: {ACTION}

```

Now generate a description of the robot's action.

**2) Grounded Preference and Task Goal Generation:** With the generated language description of the demonstration, we employ Prompt 17 to generate grounded preference and language summary of the demonstration and Prompt 18 to update the task goals.

**Prompts used:**

## Grounded Preference Prompt

You are a helpful assistant. You are skilled at taking things people say off the cuff and without context, and specifying exactly what they mean in unambiguous, clear language.

I showed a person a video of a robot doing a task and asked them to give feedback to/about the robot. You will be given:

1. Description of the task
2. Frame-by-frame description of the video
3. The person's feedback - could be ambiguous, confusing, overly long, overly short, full of errors, etc.

You need to provide:

1. A summary of the video - descriptive, complete, concise.
2. A rewrite of the feedback that is unambiguous, contextualizes the person's feedback in the video/task description, uses standard language, and directs the robot to do exactly what the person \* meant\* to ask for.

### # Feedback grounding examples

UNGROUNDED FEEDBACK 1: Not that one!  
GROUNDED FEEDBACK 1: The robot moved Blue Cube to the right. It should not - it should move Red Cube to the right.  
EXPLANATION 1: The person says "not that one" and there are two cubes in the scene, meaning they appear to have liked the action, but not the specific cube it was being done on. So, I added in direct references to the Blue Cube and the Red Cube. Since it was the Blue Cube that was moved to the right and the person clearly wanted the other option, I said not to do that and to instead move the Red Cube to the right.

UNGROUNDED FEEDBACK 2: Hmm, I like that the it move arm like that and put banana smoothly? but can it put banana in another one?

GROUNDED FEEDBACK 2: Arm movement is good, but put Banana in Shelf 2, Shelf 3, or Shelf 4.

EXPLANATION 2: The person likes the arm movement. They want the banana to be put in another "one" - since it was previously put on a shelf, this means they want it put in a different shelf. Previously it was shelf 1, so now I ask for Shelves 2, 3, or 4. They also liked the way the robot put the Banana in Shelf 1, but now they're asking for it to be put in a different one, so even though they liked it previously, I don't

ask for that now.

UNGROUNDED FEEDBACK 3: the block can go further  
GROUNDED FEEDBACK 3: Move Cube 1 further to the right.

EXPLANATION 3: The person referenced a "block". There's nothing in the description called a "block", but there is a "cube", which is a synonym. They want it moved further but don't specify where, which suggests they want it moved further in the original direction. That was to the right, so I preserve that here.

# Task description  
{CURRENT TASK GOAL}

# Video description  
{LANGUAGE DESCRIPTION OF THE DEMO}

# Feedback  
"{RAW HUMAN FEEDBACK}"

# Your task

1. Think step by step to briefly summarize the demonstration, then go through the checklist, then give me your final version of the feedback, grounded to the description.
2. Make sure your grounded feedback has a directive tone.
3. Use standard, unambiguous language over using the person's own language.
4. Do not have ANY ambiguous objects. ALWAYS use the official term for an object if it has one.

### CHECKLIST:

- The feedback may not be ordered, even if it contains multiple parts. Did you assume order inappropriately?
- The person might compliment something about the past. Don't conflate that with what they're asking for \*now\*. Did you make sure to isolate only the current instructions, and remove things they like but don't want to keep?
- The person will NEVER reference something not in the video. If they use a word you don't think is in the video, YOU ARE WRONG. Did you figure out what they were talking about? Did you replace any unexpected terms with official terms from the description?

### # Output

JSON format:

```
{
 "summary": "<SUMMARY>",
 "explanation": "<EXPLANATION>",
 "feedback": "<GROUNDED FEEDBACK>",
}
```

### Task Goal Update Prompt

You are a helpful assistant that is excellent at interpreting what humans are asking for. You will be shown three phrases:

1. A task description that was attempted by a robot
2. A description of the robot's attempted demonstration
3. Original feedback the person gave after watching the robot make the attempt.
4. Grounded feedback that has been rewritten to be clear and unambiguous.

Your job:

- If the person's feedback changes the task itself such that the original task description no longer applies, rewrite the task description.
- If the person's feedback adds to the task, then add the new information to the task description.
- However, if the person's feedback doesn't change the task and only comments on the robot's execution, then output an empty string.
- Give these in a json output.

```
Current task description: {
task_description}
Demo description: {demo_description}
Original Feedback: {original_feedback}
Grounded Feedback: {grounded_feedback}
```

```
Your output should be a JSON object
with the following format:
{
 "task_description": <TASK
DESCRIPTION>,
}
```

## H. Environment Specific Prompt

### 1) PushBall:

#### PushBall Setup Description

There should be a robot gripper and a ball on the table. In the 3D coordinate of the projects [x,y,z], x represents left and right positive is left, negative is right, y represents forward and backward, positive is forward, negative is backward, and z represents height. z = 0 represents the table surface. The radius of the sphere is 0.06. Position is measured at each object's center. Expect errors in the measurement.

### 2) PlaceSphere2BinWide:

#### PlaceSphere2BinWide Setup Description

There should be a robot gripper, a sphere, and two bins on the table. In the 3D coordinate of the projects [x,y,z], x represents forward and backward, positive is forward, y represents left and right positive is left, negative is right, z represents height. z = 0 represents the table surface. The radius of the sphere is 0.02 and each bin is 0.16 wide and 0.01 deep. Position is measured at each object's center. Expect errors in the measurement.

### 3) Stack3Cube:

#### Stack3Cube Setup Description

There are a robot gripper, a red cube, a green cube, and a purple cube on a table. The 3D coordinates of the projects [x,y,z] are defined from the viewer's perspective: the x-axis represents forward and backward, with positive values being closer and negative values farther away from the viewer; the y-axis denotes horizontal direction, with negative values to the left and positive to the right of the viewer. The z-axis measures height, where z=0 corresponds to the table surface. Each cube is 0.04 by 0.04 by 0.04. Position is measured at each object's center. Expect errors in the measurement.

#### Stack3Cube Information Keys

- `red\_cube\_pos`: 3D coordinate of red\_cube
- `green\_cube\_pos`: 3D coordinate of green\_cube
- `purple\_cube\_pos`: 3D coordinate of purple\_cube
- `is\_red\_cube\_grasped`: whether red\_cube is grasped by the robot
- `is\_green\_cube\_grasped`: whether green\_cube is grasped by the robot
- `is\_purple\_cube\_grasped`: whether purple\_cube is grasped by the robot
- `gripper\_pos`: 3D coordinate of the robot's gripper

### 4) PutObjectInDrawer:

#### PutObjectInDrawer Setup Description

There should be a robot gripper, a red apple, a red soup can, and a drawer on

the floor. Objects are roughly 0.05 in height and width. Object positions are measured at the center of the object. The 3D coordinates of the projects [x,y,z] are defined from the viewer's perspective: the x-axis represents forward and backward, with positive values being closer and negative values farther away from the viewer; the y-axis denotes horizontal direction, with negative values to the left and positive to the right of the viewer. The z-axis measures height, where z=0 corresponds to the floor. The bottom drawer is facing the right (+y direction). It's open when the scene starts. The drawer is 0.36 wide, 0.22 deep, and 0.16 high. In other words, x = drawer\_pos[0] + 0.18 is the left edge of the drawer, x = drawer\_pos[0] - 0.18 is the right edge of the drawer, y = drawer\_pos[1] + 0.11 is the drawer front, z = drawer\_pos[2] + 0.16 is the top of the drawer, and z = drawer\_pos[2] is the bottom of the drawer. The robot is placed on the floor and cannot reach the inside of the drawer. To put an object in the drawer it must be dropped from above.

#### PutObjectInDrawer Information Keys

- `apple\_pos`: 3D coordinate of apple
- `soup\_can\_pos`: 3D coordinate of soup\_can
- `is\_apple\_grasped`: whether apple is grasped by the robot
- `is\_soup\_can\_grasped`: whether soup\_can is grasped by the robot
- `gripper\_pos`: 3D coordinate of the robot's gripper
- `drawer\_handle\_pos`: 3D coordinate of the bottom drawer handle
- `drawer\_pos`: 3D coordinate of the center bottom of the drawer
- `drawer\_open\_offset`: how much the drawer is open, measured as the distance between the drawer's position now and when it is fully closed

#### 5) ObjectToBin:

##### ObjectToBin Setup Description

There should be a robot gripper, an apple, an orange, a baseball, a tennis ball, and two bins on the table. One bin is light blue and one is white. The 3D coordinates of the projects [x,y,z] are defined from the viewer's perspective: the x-axis represents forward and backward, with positive values being closer and negative values farther away

from the viewer; the y-axis denotes horizontal direction, with negative values to the left and positive to the right of the viewer. The z-axis measures height, where z=0 corresponds to the table surface. Each object is about 0.05 in diameter. Each bins are 0.20 by 0.20 by 0.02 in size. Position is measured at each object's center. Expect errors in the measurement.

#### ObjectToBin Information Keys

- `apple\_pos`: 3D coordinate of apple
- `orange\_pos`: 3D coordinate of orange
- `baseball\_pos`: 3D coordinate of baseball
- `tennis\_ball\_pos`: 3D coordinate of tennis\_ball
- `blue\_bin\_pos`: 3D coordinate of blue\_bin
- `white\_bin\_pos`: 3D coordinate of white\_bin
- `is\_apple\_grasped`: whether apple is grasped by the robot
- `is\_orange\_grasped`: whether orange is grasped by the robot
- `is\_baseball\_grasped`: whether baseball is grasped by the robot
- `is\_tennis\_ball\_grasped`: whether tennis\_ball is grasped by the robot
- `gripper\_pos`: 3D coordinate of the robot's gripper

#### I. Baselines Prompts

##### Eureka Prompt Template

We are going to use a Franka Panda robot to complete given tasks. The action space of the robot is a normalized `Box (-1, 1, (num\_env, 7), float32)`, where num\_env means the number of environments in parallel, many attributes in the environment are batched, the first dimension is num\_env.

```
Environment Code:
{environment_code}
```

```
Maniskill Doc:
{reward_guidelines}
```

```
Previous Implementations:
```

```
Previous reward function:
```python  
{previous_reward}  
```
```

Your reward function code has been analyzed, the feedback is as follows:

```
Human Feedback:
{human_feedback}

Objective Feedback:
{objective_feedback}
```

Please carefully analyze the policy feedback and provide a new, improved reward function that can better solve the task. Some helpful tips for analyzing the policy feedback:

- (1) If the success rates are always near zero, then you must rewrite the entire reward function

Please generate a reward function that follows all guidelines and addresses the human feedback. The code output should be formatted as a python code string: ````python ... ````.

- "compute\_dense\_reward": containing the complete reward function code

The functions MUST have these EXACT signatures:

```
def compute_dense_reward(self: BaseEnv,
obs: Any, action: torch.Tensor, info:
Dict[str, torch.Tensor]) -> torch.Tensor
 #Encodes reward for each possible
 action based on `evaluate` output
 dictionary and other current environment
 info (environment instance attributes).
```

#Incorporates human feedback as given.

```
#Obeys the following structure:
#1. Stage reward
 - Task is split into stages and
 reward is given to the agent gradually,
 encouraging it to complete each stage.
 The reward accumulates.
 - Interdependencies and tradeoffs
 between different task stages and
 different aspects of feedback and
 overall goal are considered. Reward
 design is not overall counterproductive
 to meet short-term goals.
#2. Return reward value
Your implementation here
pass
...
The function should:
```

1. Match the exact function signatures shown above
2. Handle batched operations correctly (num\_env dimension)
3. Include comprehensive comments
4. Follow the reward function best practices
5. Be consistent with the interface of the previous implementations while incorporating the requested changes

The code output should be formatted as a python code string: ````python ... ````.

### Text2Reward Prompt Template

We are going to use a Franka Panda robot to complete given tasks. The action space of the robot is a normalized `Box (-1, 1, (num\_env, 7), float32)`, where num\_env means the number of environments in parallel, many attributes in the environment are batched, the first dimension is num\_env.

```
Task-Specific Environment:
{environment_description}
```

```
Available Objects and Their Properties:
```

```
{env_class_desc}
```

```
Maniskill Doc:
{reward_guidelines}
```

```
Previous Implementations:
```

Previous reward function:  
```python  
{previous_reward}
```

```
Human Feedback:
{human_feedback}
```

Please generate a reward function that follows all guidelines and addresses the human feedback. The code output should be formatted as a python code string: ````python ... ````.

- "compute\_dense\_reward": containing the complete reward function code

The functions MUST have these EXACT signatures:

```
def compute_dense_reward(self: BaseEnv,
obs: Any, action: torch.Tensor, info:
Dict[str, torch.Tensor]) -> torch.Tensor
 #Encodes reward for each possible
 action based on `evaluate` output
 dictionary and other current environment
 info (environment instance attributes).
```

#Incorporates human feedback as given.

```
#Obeys the following structure:
#1. Stage reward
 - Task is split into stages and
 reward is given to the agent gradually,
 encouraging it to complete each stage.
```

The reward accumulates.

- Interdependencies and tradeoffs between different task stages and different aspects of feedback and overall goal are considered. Reward design is not overall counterproductive to meet short-term goals.

```
#2. Return reward value
Your implementation here
pass
...
```

The function should:

1. Match the exact function signatures shown above
2. Handle batched operations correctly (num\_env dimension)
3. Include comprehensive comments
4. Follow the reward function best practices
5. Be consistent with the interface of the previous implementations while incorporating the requested changes

The code output should be formatted as a python code string: "```python ... ```".

### Text2Reward Environment Class Description

```
#class PandaRobot:
 self.tcp.pose.p: torch.Tensor([
 num_env, 3]) # Batched by the number of
 environment, indicate the 3D position of
 the robot's gripper
 self.tcp.pose.q: torch.Tensor([
 num_env, 4]) # Batched by the number of
 environment, indicate the quaternion of
 the robot's gripper
 self.robot.qpos: torch.Tensor([
 num_env, 9]) # Batched by the number of
 environment, indicate the joint
 positions (last 2 for gripper) of the
 robot at this key frame
 self.robot.qvel: torch.Tensor([
 num_env, 9]) # Batched by the number of
 environment, indicate the joint
 velocities (last 2 for gripper) of the
 robot at this key frame
 def is_grasping(self, object: Actor,
 min_force=0.5, max_angle=85): -> torch.
 Tensor([num_env, 1], bool) # Batched by
 the number of environment, check if the
 robot is grasping an object

class RigidObject:
 self.pose.p: torch.Tensor([num_env,
 3]) # Batched by the number of
 environment, indicate the 3D position of
 the simple rigid object in each
 environment
 self.pose.q: torch.Tensor([num_env,
 4]) # Batched by the number of
 environment, indicate the quaternion of
```

the simple rigid object in each environment

```
def get_angular_velocity(self,) ->
 torch.Tensor([num_env, 3]) # Batched by
 the number of environment, indicate the
 angular velocity of the simple rigid
 object
def get_linear_velocity(self,) ->
 torch.Tensor([num_env, 3]) # Batched by
 the number of environment, indicate the
 linear velocity of the simple rigid
 object
self.get_first_collision_mesh().
bounding_box.bounds: np.ndarray[(2, 3)]
non-batched, indicate the bounding box
of the simple rigid object
```

```
class TargetObject:
 self.pose.p: torch.Tensor([num_env,
 3]) # Batched by the number of
 environment, indicate the 3D position of
 the TargetObject in each environment
 self.pose.q: torch.Tensor([num_env,
 4]) # Batched by the number of
 environment, indicate the quaternion of
 the TargetObject in each environment
```

```
class LinkObject:
 self.pose.p: torch.Tensor([num_env,
 3]) # Batched by the number of
 environment, indicate the 3D position of
 the link object in each environment
 self.pose.q: torch.Tensor([num_env,
 4]) # Batched by the number of
 environment, indicate the quaternion of
 the link object in each environment
 def get_angular_velocity(self,) ->
 torch.Tensor([num_env, 3]) # Batched by
 the number of environment, indicate the
 angular velocity of the link object
 def get_linear_velocity(self,) ->
 torch.Tensor([num_env, 3]) # Batched by
 the number of environment, indicate the
 linear velocity of the link object
 self.qpos : torch.Tensor([num_env,],
 float) # Batched by the number of
 environment, indicate the position of
 the link object joint
 self.qvel : torch.Tensor([num_env,],
 float) # Batched by the number of
 environment, indicate the velocity of
 the link object joint
```

```
class ArticulateObject:
 self.pose.p: torch.Tensor([num_env,
 3]) # Batched by the number of
 environment, indicate the 3D position of
 the articulate object in each
 environment
 self.pose.q: torch.Tensor([num_env,
 4]) # Batched by the number of
 environment, indicate the quaternion of
 the articulate object in each
 environment
 self.qpos : torch.Tensor([num_env,
```

```

9]) # Batched by the number of
environment, indicate the joint
positions of the articulate object at
this key frame
 self.qvel : torch.Tensor([num_env,
9]) # Batched by the number of
environment, indicate the joint
velocities of the articulate object at
this key frame
 self.get_first_collision_mesh().
bounding_box.bounds: np.ndarray[(2, 3)]
non-batched, indicate the bounding box
of the articulate object

```

### Documentation For Eureka and Text2Reward

# Documentation of classes, methods, and properties you can use when implementing `compute\_dense\_reward`

This is a parallel training environment with many episodes. Each pose, boolean description of the scene, etc. is therefore a `torch.Tensor` where the first dimension is the \*batch dimension\*. Each episode is independent, so you must calculate reward separately for each one. Specifically:

- `reward` is a `torch.Tensor` of scalar reward values for the batch of episodes. The first dimension is a batch of episodes, and the second dimension is the scalar reward value for that individual episode.

- For example, if you want to give a reward boost of 5.0 to exactly the episodes where the object is grasped, and you have already computed the `is\_obj\_grasped` tensor, you can say `reward["is\_obj\_grasped"] += 5.0`.

```

`Actor` class
Non-robot objects in scene are
subclasses of `Actor`.
Properties
- `px_body_type`: `Literal["kinematic", "static", "dynamic"]` indicating physics
behavior - static (immovable), dynamic (not
physics-affected), kinematic (not
physics-affected).
- The robot cannot move "static" and "kinematic" objects. If a feedback asks
you to change their locations, reject
that part.
- `name`: `str` acting as the unique
identifier for the actor
- `merged`: `bool` indicating if the
actor is a composite of multiple other
actors
- `pose`: `Pose` object representing the
current state
 - `Pose` object: dataclass
 - `pose.p` is a position

```

- `pose.q` is a quaternion indicating orientation
  - `pose.raw\_pose` is concatenation of `p` then `q`
    - `Pose.create\_from\_pq(p=p, q=q)` returns a new `Pose` object at that `p` and `q`.

### Instance methods (called with `<actor\_instance>.method\_name(<params>)`)

- `get\_state`:
  - `self.<actor\_instance>.get\_state()[:, 7:10]` contains linear velocity
    - `self.<actor\_instance>.get\_state()[:, 10:13]` contains angular velocity
- `is\_static(lin\_thresh=1e-2, ang\_thresh =1e-1)`: boolean check if actor is static based on velocity thresholds
  - `lin\_thresh`: linear velocity threshold
    - `ang\_thresh`: angular velocity threshold

## Agent class

`BaseAgent` class for the robot. The robot is a 7-DoF arm-and-two finger gripper. Degrees of freedom: arm position, arm orientation, and gripper open/close.

- Note that you will see `tcp` throughout the code, with its specific position being queried. `tcp` stands for Tool Center Point, the center between the two fingers. `tcp.pose` attributes tells you where the gripper is positioned.

### Properties

- `self.agent.controller`: currently activated controller
- `self.agent.action\_space`: position/orientation/state that controller has been sent to in the latest action, concatenated for the two controllers (arm and end-effector)

### Methods

- `self.agent.get\_state()`: returns a dictionary with the following keys:
  - "robot\_root\_pose": root pose
  - "robot\_root\_vel": root velocity
  - "robot\_root\_qvel": root angular velocity
  - "robot\_qpos": joint position
  - "robot\_qvel": joint velocity
  - "controller": output of `controller.get\_state()`, which contains target positions and orientations of the currently activated controller
- `self.agent.is\_grasping(object: Union[Actor, None] = None)`: boolean check if agent is grasping object
- `is\_static(threshold: float)`: boolean check if robot is static (within given threshold) in terms of q velocity
- `self.agent.robot.get\_qlimits()[0, -1, 1] \* 2` gripper width, i.e. max possible opening

```

Other
- `tcp` stands for "tool center point" - it is the point between the robot's grippers and is TODO whole robot
- Like `reward` and the values of `info`, quantities are tensors over the batch. For example, `pose` is a tensor where the first dimension is the batch of multiple episodes, and the rest describe the pose of that episode.
- IMPORTANT: here, x is the front-and-back axis, y is the left-and-right axis, and z is the up-and-down axis. Typically, x and y are flipped - check your work!

```

### LMPC Prompt Template

**## High-Level Description:**  
 You are an expert robot reward function programmer.  
 Your goal is to write improved reward functions for a Franka Panda robot arm with a gripper to fulfill tasks based on feedback and previous implementations. You will analyze feedback and create reward functions that better guide the robot to accomplish its tasks.

**## Robot Environment Details:**  
 We are using a Franka Panda robot to complete given tasks. The action space of the robot is a normalized `Box(-1, 1, (num\_env, 7), float32)`, where `num\_env` means the number of environments in parallel. Many attributes in the environment are batched, with the first dimension being `num\_env`.

The robot is a 7-DoF arm with a two-finger gripper. Degrees of freedom include arm position, arm orientation, and gripper open/close. The Tool Center Point (tcp) is the center between the two fingers.

**## Coordinate System:**  
 The coordinate system is right-handed and three-dimensional:  

- x-axis: front-and-back
- y-axis: left-and-right
- z-axis: up-and-down (aligned with gravity)

Note that x and y are typically flipped in standard notation - check your work carefully!

**## Previous Implementation and Feedback:**  
 For each task, you will be provided with:

1. A previous reward function

```

implementation (`compute_dense_reward`)
2. Human feedback on the previous implementation (`human_feedback`)

```

**## Your Task:**  
 You must carefully analyze the feedback and provide a new, improved reward function that better solves the task. Your function should:

1. Match the exact function signature:  
`...`

```

def compute_dense_reward(self: BaseEnv,
obs: Any, action: torch.Tensor, info:
Dict[str, torch.Tensor]) -> torch.Tensor
...

```

### ## Available APIs:

**### Actor Class (Non-robot objects in scene)**

**#### Properties:**

- `px\_body\_type`: Physics behavior type ("kinematic", "static", "dynamic")
- `name`: Unique identifier
- `merged`: Boolean indicating if the actor is composite
- `pose`: Position and orientation
  - `pose.p`: Position
  - `pose.q`: Quaternion orientation
  - `pose.raw\_pose`: Concatenation of p and q

**#### Methods:**

- `get\_state()[:, 7:10]`: Linear velocity
- `get\_state()[:, 10:13]`: Angular velocity
- `is\_static(lin\_thresh=1e-2, ang\_thresh=1e-1)`: Boolean check if actor is static

**### Agent Class (Robot)**

**#### Properties:**

- `self.agent.controller`: Currently activated controller
- `self.agent.action\_space`: Position/orientation/state of controllers

**#### Methods:**

- `self.agent.get\_state()`: Returns robot state dictionary
- `self.agent.is\_grasping(object)`: Boolean check if agent is grasping object
- `is\_static(threshold)`: Boolean check if robot is static
- `self.agent.robot.get\_qlimits() [0, -1, 1] \* 2`: Gripper width

**## Important Notes:**

- `tcp` is the Tool Center Point (center between robot's grippers)
- All quantities are tensors over the batch dimension
- The robot cannot move "static" and "

```

kinematic" objects

Output Format:
Your output should be formatted as a
Python code string: "```python ...
- The code should contain the complete `compute_dense_reward` function

Robot Code Writing Hints:
- Do not use any functions or object
names besides the ones mentioned above.

Chat Turn Example:

Environment code:

```python
class CubeAndTargetEnv(BaseEnv):
    """
    **Task Description:** A simple task where the objective is to pull a cube onto a target.

    **Randomizations:** - the cube's xy position is randomized on top of a table in the region [0.1, 0.1] x [-0.1, -0.1]. - the target goal region is marked by a red and white target. The position of the target is fixed to be the cube's xy position - [0.1 + goal_radius, 0]

    **Success Conditions:** - the cube's xy position is within goal_radius (default 0.1) of the target's xy position by euclidean distance.
    """

    _sample_video_link = "https://github.com/haosulab/ManiSkill/raw/main/figures/environment_demos/PullCube-v1_rt.mp4"
    SUPPORTED_ROBOTS = ["panda", "fetch"]
    agent: Union[Panda, Fetch]
    goal_radius = 0.1
    cube_half_size = 0.02

    def __init__(self, *args, robot_uids="panda", robot_init_qpos_noise=0.02, **kwargs):
        self.robot_init_qpos_noise = robot_init_qpos_noise
        super().__init__(*args, robot_uids=robot_uids, **kwargs)

        @property
        def _default_sensor_configs(self):
            pose = look_at(eye=[0.3, 0, 0.6], target=[-0.1, 0, 0.1])
            return [CameraConfig("base_camera", pose, 128, 128, np.pi / 2, 0.01, 100)]

        @property
        def

```

```

_load_default_human_render_camera_configs(self):
    pose = look_at([0.6, 0.7, 0.6],
[0.0, 0.0, 0.35])
    return CameraConfig("render_camera", pose, 512, 512, 1, 0.01, 100)

def _load_agent(self, options: dict):
    super().__load_agent(options,
sapien.Pose(p=[-0.615, 0, 0]))

def _load_scene(self, options: dict):
    self.table_scene =
TableSceneBuilder(
    env=self,
    robot_init_qpos_noise=self.
robot_init_qpos_noise
)
    self.table_scene.build()

    # create cube
    self.obj = actors.build_cube(
        self.scene,
        half_size=self.
cube_half_size,
        color=np.array([12, 42, 160,
255]) / 255,
        name="cube",
        body_type="dynamic",
        initial_pose=sapien.Pose(p
=[0, 0, self.cube_half_size]),
    )

    # create target
    self.goal_region = actors.
build_red_white_target(
        self.scene,
        radius=self.goal_radius,
        thickness=1e-5,
        name="goal_region",
        add_collision=False,
        body_type="kinematic",
    )

    def _initialize_episode(self,
env_idx: torch.Tensor, options: dict):
        with torch.device(self.device):
            b = len(env_idx)
            self.table_scene.initialize(
env_idx)
            xyz = torch.zeros((b, 3))
            xyz[:, :, :2] = torch.rand((b,
2)) * 0.2 - 0.1
            xyz[:, :, 2] = self.
cube_half_size
            q = [1, 0, 0, 0]

            obj_pose = Pose.
create_from_pq(p=xyz, q=q)
            self.obj.set_pose(obj_pose)

            target_region_xyz = xyz -

```

```

        torch.tensor([0.1 + self.goal_radius, 0,
                      0]))
    target_region_xyz[..., 2] =
1e-3
        self.goal_region.set_pose(
            Pose.create_from_pq(
                p=target_region_xyz,
                q=euler2quat(0, np.
pi / 2, 0),
            )
        )
        self.object_list = {"cube": self.obj,
                            "goal": self.goal_region}
    def evaluate(self):
        is_obj_placed = (
            torch.linalg.norm(
                self.obj.pose.p[..., :2]
            - self.goal_region.pose.p[..., :2],
            axis=1
            )
            < self.goal_radius
        )
        return {
            "success": is_obj_placed,
        }
    def _get_obs_extra(self, info: Dict):
        obs = dict(
            tcp_pose=self.agent.tcp.pose.
raw_pose,
            goal_pos=self.goal_region.
pose.p,
        )
        if self._obs_mode in ["state", "state_dict"]:
            obs.update(
                obj_pose=self.obj.pose.
raw_pose,
            )
        return obs
    def compute_dense_reward(self, obs: Any, action: Array, info: Dict):
        # grippers should close and pull
        from behind the cube, not grip it
        # distance to backside of cube (+
        2*0.005) sufficiently encourages this
        tcp_pull_pos = self.obj.pose.p +
        torch.tensor(
            [self.cube_half_size + 2 *
0.005, 0, 0], device=self.device
        )
        tcp_to_pull_pose = tcp_pull_pos -
        self.agent.tcp.pose.p
        tcp_to_pull_pose_dist = torch.
linalg.norm(tcp_to_pull_pose, axis=1)
        reaching_reward = 1 - torch.tanh(
            5 * tcp_to_pull_pose_dist)
        reward = reaching_reward

```

```

reached = tcp_to_pull_pose_dist
< 0.01
obj_to_goal_dist = torch.linalg.
norm(
    self.obj.pose.p[..., :2] -
    self.goal_region.pose.p[..., :2], axis=1
)
place_reward = 1 - torch.tanh(5 *
obj_to_goal_dist)
reward += place_reward * reached
reward[info["success"]] = 3
return reward

def compute_normalized_dense_reward(
    self, obs: Any, action: Array, info: Dict):
    max_reward = 3.0
    return self.compute_dense_reward(
        obs=obs, action=action, info=info) /
max_reward

def get_fitness_score(self):
    # get the fitness score of the
    current episode
    # returns a tensore of shape (
batch_size, )
    # currently, the fitness score
    is the distance between the cube and the
    goal
    # fitness score always the
    higher the better so we return the
    negative distance
    return -torch.linalg.norm(
        self.obj.pose.p[..., :2] -
        self.goal_region.pose.p[..., :2], axis=1
    )
```
Previous Implementations:
Previous reward function:
```python
def compute_dense_reward(self, obs,
                        action, info):
    reward = torch.zeros_like(info["
task_completed"], dtype=torch.float32)
    # Simple reward for moving toward
    object
    target_pos = self.object.pose.p
    gripper_pos = self.agent.tcp.pose.p
    distance = torch.norm(gripper_pos -
target_pos, dim=-1)
    reward -= distance * 0.1
    return reward
```
Your reward function code has been
analyzed, the feedback is as follows:
Human Feedback:
The robot moves toward the object but
doesn't attempt to grasp it.

Output:
```python

```

```

def compute_dense_reward(self: BaseEnv,
obs: Any, action: torch.Tensor, info:
Dict[str, torch.Tensor]) -> torch.Tensor:

    # Initialize reward tensor for batch
    # processing
    reward = torch.zeros_like(info[""
task_completed"], dtype=torch.float32)

    target_pos = self.object.pose.p
    gripper_pos = self.agent.tcp.pose.p
    distance = torch.norm(gripper_pos -
target_pos, dim=-1)
    reward -= distance * 0.2 # Increased weight for faster approach

    is_grasping = self.agent.is_grasping
    (self.object)
    reward[is_grasping] += 1.0 # Reward
    for successful grasp

    if "grasped_duration" in info:
        reward += info["grasped_duration"]
    ] * 0.05 # Small reward for
    maintaining grasp

    return reward
```
New Chat Session
Environment code:
```python
{environment_code}
```
Previous Implementations:
Previous reward function:
```python
{compute_dense_reward}
```

Your reward function code has been analyzed, the feedback is as follows:
Human Feedback:
```python
{human_feedback}
```

Your output should be formatted as a Python code string: "```python ... ```" - The code should contain the complete `compute_dense_reward` function

Output:

```

#### J. Error Correction Prompts

##### Short Horizon Error Correction Prompt

You are being given code that is a training environment for a reinforcement learning-based robot. Code details:  
1. `\_load\_scene`, `\_initialize\_episode`, and all the methods called by them, set

up the scene.  
2. `evaluate` calculates information about the current environment state in a dictionary. Its output dictionary is given to `compute\_dense\_reward` in the parameter `info`.  
3. `compute\_dense\_reward` outputs a final reward.

The code is as follows:

```

```python
{generated_env_code}
```

```

This code has an error in it that you need to fix. The stack trace is as follows:  
```python
{error_trace}
```

The line that threw the error is `{{error\_line}}`.

Please fix it.

1. You cannot take debugging steps, you have to fix it without more info.
2. You should only edit `evaluate` and `compute\_dense\_reward` and any of their helper methods. Enclose them in markdown  
```python <your code> ```` delimiters.
3. Don't use "```python ... ```" delimiters anywhere else in your response. You can use `<code>` if needed.
3. If you would absolutely have to edit other methods to make the code work, you should instead say "this requires edits to restricted parts of the code. I can't continue."
4. Follow the documentation below. Do not violate it.
5. OUTPUT THE WHOLE REVISED FUNCTION, NOT JUST A SNIPPET.

{documentation}

Long Horizon Error Correction Prompt

You are being given code that is a training environment for a reinforcement learning-based robot. Code details:

1. `_load_scene`, `_initialize_episode`, and all the methods called by them, set up the scene.
2. `evaluate` calculates information about the current environment state in a dictionary. Its output dictionary is given to `skill_reward` in the parameters `prev_info` and `cur_info` - each represents `evaluate` called on a different environment state.
3. `prev_info` and `cur_info` go through

a conversion that turns their `torch.Tensor` values with batch dimensions into `numpy.ndarray` values WITHOUT a batch dimension.
3. `skill_reward` outputs a final reward.

The code is as follows:

```
```python
{generated_env_code}
```
```

This code has an error in it that you need to fix. The stack trace is as follows:

```
```python
{error_trace}
```
```

The line that threw the error is {
error_line}.

Please fix it.

1. You cannot take debugging steps, you have to fix it without more info.
2. You should only edit `evaluate` and `skill_reward` and any of their helper methods.
3. If you would absolutely have to edit other methods to make the code work, you should instead say "this requires edits to restricted parts of the code. I can't continue."
4. OUTPUT THE WHOLE REVISED FUNCTION, NOT JUST A SNIPPET.

SURVEYS

We conduct three types of surveys:

- 1) Robot Video Preference, as shown in Survey 1: This survey collects human preference on robot trajectory videos.
- 2) Video Quality Evaluation, as shown in Survey 2: This survey evaluates how well newly trained robot behaviors align with preference from previous videos.
- 3) Preference Evaluation, as shown in Survey 3: This survey collects human preferences among videos generated by different methods.

Robot Video Preference

Watch a robot do a task at the video we sent you, then give feedback.

* Indicates required question

Required Questions:

1. What's your name? Make sure to enter your name the same way every single time.
*
2. Which video are you giving feedback for? Copy-paste the .mp4 file. So if the file is named "video_name.mp4", put "video_name" here. *

3. Describe the video *

4. Give feedback. Again, be natural! Speak the way you'd want to speak to your personal robot assistant. Even if the task isn't inherently interesting, feel free to be creative - ask to change the order, the location, and more. *

Task Overview:

You're going to watch a robot do a task. Your job is to give the robot feedback.

Purpose:

- The robot's execution might have problems
- Even if technically fine, it might not meet your preferences
- We want feedback on what you do and don't like
- Goal is to make the robot adapt to you, not vice versa

CRUCIAL GUIDELINES:

1. Procedure:
 - Watch the entire video
 - Describe the video in the first answer box
 - Enter feedback in the second answer box
2. Focus on Outcomes:
 - Don't guess how the robot works
 - Don't suggest technical mechanisms
 - Focus on preferences and corrections
 - Describe what you want/don't want
3. Feedback Limits:
 - Maximum one feedback on overall behaviors
 - Maximum one feedback on object orientation
 - No feedback on speed (technical limitation)
4. Communication Style:
 - Speak naturally
 - Use everyday language
 - Be specific
 - Context-dependent statements are acceptable

EXAMPLE SCENARIO:

Robot sweeping crumbs task

High Quality Feedback Examples:

- "The robot didn't finish sweeping. There are crumbs all over the place. The crumbs near the couch and TV should have gotten swept up."
- "I like that the robot brought the crumbs close to the trash can. That's a good idea."
- "Ew, I hate that the robot just left

the crumbs near the trash. That whole corner of the kitchen is so gross."
- "I like that the crumbs are in the kitchen, but now it should put the broom away."

Low Quality Feedback Examples:

- "The robot should work on getting its arm to reach further so it can sweep up more crumbs."
- "This is dumb. It should be calculating more precise trajectories."

Challenging but Acceptable:

- "Not that one, the other one." (If context makes meaning clear)

Note: Your feedback can be longer than examples and include multiple ideas. Be thorough and specific.

This content is neither created nor endorsed by Google.

Forms

Video Quality Evaluation

Earlier, you watched a video of a robot doing a task and gave feedback. We tried to incorporate your feedback, and sent you one or more options in your options-to-choose-from folder.

Instructions:

1. Choose the video you think is best from that folder.
2. For that video only, fill out this form that asks about your satisfaction with the update.

* Indicates required question

Basic Information:

1. Copy-paste the name of the video you liked best here. Remove ".mp4", as you do in the other form. *

Feedback Implementation Assessment:

2. In the most recent video, did the robot incorporate your feedback that ** wasn't met in the previous video**? *
Mark only one oval.
 - No - the robot didn't incorporate any part of my feedback
 - Some - the robot incorporated some parts of my feedback, but not all of them.
 - Yes - the robot incorporated all parts of my feedback.

3. In the most recent video, to what degree did the robot incorporate your feedback that **wasn't met in the

previous video**? *
Mark only one oval.

- None - the robot didn't incorporate my feedback
- Medium - the robot incorporated my feedback to a moderate degree but not fully.
- High - the robot incorporated my feedback fully.

4. In the most recent video, did the robot get worse with respect to any of your feedback **compared to the previous video**? *

Mark only one oval.

- No - it did not get worse with respect to any part of my feedback.
- Some - it got worse with respect to some parts of my feedback, not others.
- Yes - it got worse with respect to all parts of my feedback.

5. In the most recent video, did the robot change its performance in ways you didn't ask for **compared to the previous video**? *

Specifically, change even if not directly/purely negating your feedback? For example, if you asked the robot to be neater and smoother but didn't say anything about speed, and the robot became noticeably faster in this video compared to the last one, you would say yes. Else, no.

Mark only one oval.

- Yes *Skip to question 7*
- No *Skip to question 11*

Progress Assessment:

6. How much **progress** do you feel the robot made on the goal you wanted? * If it got halfway toward the goal your feedback was asking for, that would be a 5.

Mark only one oval.

1 2 3 4 5 6 7 8 9 10

Did the goal fully o o o o o o o o o o
The robot did something you didn't ask for

Unasked Changes:

7. Which of these statements best describes your feelings about the change(s) you didn't ask for? *

Mark only one oval.

- I strongly dislike them.
- I somewhat dislike them.
- I feel neutrally about them.
- I somewhat like them.
- I strongly like them.

8. Was the robot doing these same things you didn't ask for in the previous video? *

Mark only one oval.

- Yes
- No

9. In the most recent video, does the robot's performance directly contradict your feedback? *

Mark only one oval.

- Yes
- No

10. Describe the changes you saw that you felt you didn't ask for, but weren't directly/purely against your feedback. *

Satisfaction Assessment:

11. Are you more satisfied with the robot in the most recent video than you were in the previous video? *

Mark only one oval.

- Yes *Skip to question 12*
- No *Skip to question 13*

Satisfaction Level:

12. How much more satisfied are you? *

Mark only one oval.

1 2 3 4 5

Not at all o o o o Completely satisfied

13. How much more dissatisfied are you? *

Mark only one oval.

1 2 3 4 5

Not at all o o o o Completely dissatisfied

Overall Satisfaction:

14. How satisfied are you with the task overall, regardless of your feedback? *

Mark only one oval.

1 2 3 4 5

o o o o Very satisfied

This content is neither created nor endorsed by Google.

Forms

Preference Evaluation

1. Folder Name *

Please copy and paste the name of the folder.

(e.g., labtest-PlaceSphere2BinWideb44eadad34-ee940ce50d773948).

2. Please rank the videos from 1 to N based on your preference, with 1 being the best.

For example, if there are six videos, a rank of 3,4,2,1,5,6 indicates you love 4. mp4 the best.

| | 6 | 7 | 8 | 9 | 1 | 2 | 3 | 4 | 5 |
|--------|---|---|---|-----------------------|-----------------------|-----------------------|-----------------------|-----------------------|-----------------------|
| Video1 | | | | <input type="radio"/> |
| Video2 | | | | <input type="radio"/> |
| Video3 | | | | <input type="radio"/> |
| Video4 | | | | <input type="radio"/> |
| Video5 | | | | <input type="radio"/> |
| Video6 | | | | <input type="radio"/> |
| Video7 | | | | <input type="radio"/> |
| Video8 | | | | <input type="radio"/> |
| Video9 | | | | <input type="radio"/> |

Mark only one oval per row.

K. Taxonomy

Taxonomy definitions

- **3rd-person vs. 2nd-person vs. no-pov:** how the preference addresses the embodied agent
- **verbose:** concepts explained in lots of words, more than may be necessary
- **colloquial:** concepts explained colloquially, casually, or with imprecise (but not ambiguous) terms
- **context-dependent:** requires info from the demonstration or previous preferences to be understood; environment code is not sufficient
- **ambiguous:** even context is not enough, and the preference is up to interpretation (rare)
- **multi-part:** multiple concepts within one preference
- **directive vs. suggestive vs. curious:** preference tone. *Directive* is command-like, *suggestive* is phrased as a question but clearly instructional, and *curious* is a genuine question about the agent's abilities or potential
- **distraction:** contains distracting language that may be incorrectly incorporated into the reward function
- **contradiction:** preference that directly contradicts prior preference
- **preferential:** adds to or changes task requirements
- **corrective:** doesn't add to or change the task requirements, instead asks for improvement on current requirements
- **preferential:** adds to or changes the task requirements
- **goal-related:** affects the definition of success
- **behavioral:** affects other parts of the reward landscape
- **inadvertently long-horizon:** creates an impossible masking problem in the short-horizon continuous control setting
- **affirming:** positive about some aspect of the task that should be propagated
- **asking for change:** asking for some aspect to be changed
- **physically difficult:** difficult for the test agents, e.g. throwing a ball

- **physically impossible**: impossible for the test agents, e.g. picking up a ball that is much wider than the gripper.
- **multi-objective**: preference containing multiple complex goals that need to be achieved simultaneously. Restricted (and rare)
- **specific position**: complex or specific natural language description of a position
- **specific orientation**: complex or specific natural language description of an orientation
- **illegal**: requires edits to code outside of `compute_dense_reward` and `evaluate`.

DETAILED METRICS

• Alignment

- **Percent more satisfied (MS)**: given a binary question asking whether or not they were more satisfied with the current video than with the previous video given their preference, for what percentage of preferences did the annotator say were more satisfied?
- **Satisfaction score (SS)**: annotators were given a five-point Likert scale to indicate their degree of (dis)satisfaction, based on their answer to the binary satisfied-yes-no question. In both cases, 1 was the smallest amount of (dis)satisfaction, and 5 was the highest amount. Satisfaction score is calculated by shifting both from 1-5 to 0-4 as 1 means neutrality, negating the Likert score value in dissatisfaction cases, and rescaling from 0 to 10.
- **Percent chosen (PC)**: when directly comparing policy rollouts on a single preference, frequency of the given method’s rollout being selected over ROSETTA’s

• Optimizability

- **Success rate (SR)**: success rate of best policy across all variants for a given preference
- **Percent success >50**: percent preferences where best policy has success rate higher than 50%

• Semantic match

- **Grounding**: normalized 7-point Likert scale score on semantic match between original and grounded preference
- **Staging**: normalized 7-point Likert scale score on semantic match between grounded preference and staging plan
- **Coding**: normalized 7-point Likert scale score on semantic match between staging plan and reward code
- **Cascading**: product of Grounding, Staging, and Coding. Generally evaluated only for preferences expert evaluators consider reasonable, given quickly compounding errors.

REINFORCEMENT LEARNING DETAILS

L. Short-Horizon Setup

We implement our approach using PPO for training agents on four short-horizon environments. The implementation is based on the ManiSkill environment, which provides a realistic

physics-based simulation platform for robotic manipulation. The policy is trained using parallel environments (`num_envs = 1024`) to improve sampling efficiency and training stability. We use state-based observation and 7-dimensional `pd_joint_delta` action.

The training hyperparameters are given in Table III. The training steps of different environments are given in Table V.

M. Long-Horizon Training Setup

a) *RL Problem Setup*: We model the robot manipulation task as a Markov decision process denoted by the set $(\mathcal{S}, \mathcal{A}, \mathcal{P}, \mathcal{R}, \gamma)$, representing the state space, the action space, the transition function, the reward function, and the discount factor. A policy π is a mapping from the observation state space \mathcal{S} to a probability distribution over the robot action space \mathcal{A} .

The observable state space \mathcal{S} consists of the position of the object in the scene, the gripper’s position, the interaction between the robot and the object (e.g., whether the robot is picking up an object), and the current stage of task progression. The observation space for each long-horizon environment is provided in Table VI.

For the action space \mathcal{A} , we use a subset of parameterized primitive skills from MAPLE [32], specifically: Pick, Place, and Push. The descriptions of these skills are provided in Table VII. The action space \mathcal{A} is 9-dimensional, where the first three values represent the probability distribution over the available skills, and the remaining six values serve as parameters for the selected skill. Each primitive skill execution typically completes within 100 low-level actions. If execution exceeds 250 low-level actions, the robot stops and retracts to its home position.

The task horizon is inferred from the generated reward function and varies depending on human feedback. The remaining RL setup is consistent with the short-horizon case.

b) *Training Setup*: We train a hierarchical policy [32] with two 512-dimensional layers using Soft Actor-Critic (SAC) [13]. Hyper-params are given in Table IV.

Training terminates early when evaluation accuracy reaches 0.9 or higher. If this threshold is not met, training continues until 200 million lower-level steps have been completed. The same training configuration is applied across all three long-horizon environments for every generated reward function, with hyperparameters optimized to minimize training time.

To further improve sample efficiency and reduce training time, we apply a balanced rollout buffer that ensures rollouts are evenly sampled across all task stages, leading to faster learning, especially for the robot to learn later stages.

| Hyperparameter | Value |
|------------------------------|-------|
| Learning rate | 3e-4 |
| Discount factor (γ) | 0.8 |
| GAE parameter (λ) | 0.9 |
| Number of minibatches | 32 |
| PPO epochs | 8 |
| Value function coefficient | 0.5 |
| Entropy coefficient | 0.0 |
| Gradient norm clipping | 0.5 |
| Target KL divergence | 0.1 |
| Actor Size | 256*2 |
| Critic Size | 256*2 |

TABLE III: PPO Hyperparameters

| Hyperparameter | Value |
|-------------------------------|-------|
| Learning rate | 3e-3 |
| Discount factor (γ) | 0.2 |
| Update Coefficient (τ) | 0.5 |
| # of Gradient Step | 8 |
| Batch Size | 1024 |
| Policy Model Size | 512*2 |

TABLE IV: SAC Hyperparameters

| Environment Name | Total Timesteps | Episode Length | Description |
|---------------------|-----------------|----------------|----------------------------|
| Pick1Cube | 10M | 50 | Cube picking |
| Pull1Cube | 10M | 50 | Cube pulling |
| PushBall | 20M | 50 | Ball pushing |
| PlaceSphere2BinWide | 100M | 200 | Sphere placement in 2 bins |

TABLE V: Short-horizon Environment Setups

| Environment | Observation Space |
|--------------------|--|
| ThreeCubes | 3D positions of the red, green, and purple cubes; grasp status of each cube; robot's gripper position; and the current stage of the task. |
| ObjectsAndDrawer | Positions of the drawer, drawer handle, apple, and soup can; grasp status of the apple and soup can; robot's gripper position; and the current stage of the task. |
| ObjectsAndBins | 3D positions and grasp status of the tennis ball, baseball, orange, and apple; positions of two bins; robot's gripper position; and the current stage of the task. |
| SphereAndBins | 3D positions and grasp status of the sphere; positions of two bins; robot's gripper position. |
| BallAndTarget | 3D positions and grasp status of the ball; positions of the target; robot's gripper position. |

TABLE VI: Observation Space for Long Horizon Environments

| Skill | Description |
|--------------|---|
| Pick | Moves the end-effector to a specified (x, y, z) location and closes the gripper to grasp an object. |
| Place | Moves the end-effector to a specified (x, y, z) location and opens the gripper to release an object. |
| Push | Moves the end-effector to a specified (x, y, z) location, then applies a displacement (δx , δy , δz) to push an object. |

TABLE VII: Parameterized Primitive Skills